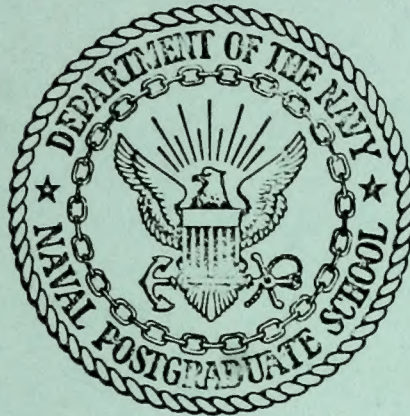


NAVAL POSTGRADUATE SCHOOL

Monterey, California



THESIS

NATURAL MODES AND FREQUENCIES OF
FREE VIBRATION OF SHELLS OF REVOLUTION

—
ANALYSIS OF A SHELL OF
LINEARLY VARYING THICKNESS

—
SATANS-III: THEORY AND USER'S MANUAL

by

Ralph Robert Nebiker

Thesis Advisor:

R.E. Ball

March 1973

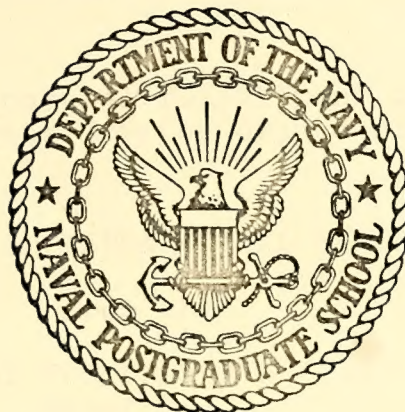
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SATANS-III: Theory and User's Manual

by

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Lieutenant, United States Navy
B.S., Stevens Institute of Technology, 1966

Submitted in partial fulfillment of the
requirements for the degree of

MASTER OF SCIENCE IN AERONAUTICAL ENGINEERING

from the

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March 1973

ABSTRACT

A digital computer program known as SATANS-III is developed as a modification to the program SATANS-I, incorporating the capability to perform free vibration analyses for the natural frequencies and modes of thin, elastic shells of revolution. The geometric and material properties of the shell may vary along the meridian. SATANS-III retains the SATANS-I capability of performing geometrically nonlinear static and dynamic analyses of arbitrarily loaded shells. The free vibration analysis employs the inverse iteration method with spectral shifts, including the capability to search a specific range of frequencies. Several example problems are solved to illustrate the program's validity and accuracy. A user's manual for SATANS-III is presented. In addition, the problem of handling a large, strongly banded, unsymmetric and occasionally singular stiffness matrix in conjunction with a singular mass matrix is treated. A discussion of several solution procedures with respect to this problem is given.

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TABLE OF SYMBOLS

a	characteristic shell reference length
b	nondimensional inplane stiffness
d	nondimensional bending stiffness
E_y	Young's modulus
E_o	Reference Young's modulus
f	natural frequency, CPS or Hz
h	shell thickness
h_o	shell reference thickness
h_1	thickness at initial edge
h_2	thickness of final edge
ht	shell height at axis of revolution
$M_s, M_\theta, M_{s\theta}$	bending and twisting moments per unit length
m	shell mass density, lb-sec ² /in ⁴
$m_s, m_\theta, m_{s\theta}$	nondimensional bending and twisting moment series coefficients
N, n	Fourier series circumferential harmonic (wave number)
$N_s, N_\theta, N_{s\theta}$	membrane forces per unit length
$\hat{N}_{s\theta}$	effective shear force
p	nondimensional pressure load series coefficient
\hat{Q}_s	effective transverse force
q, q_s, q_θ	normal, meridional and circumferential components of applied pressure loading
R_s, R_θ	principal radii of curvature
r	normal distance from the axis of shell

\bar{r}	normal distance from shell axis used in nondimensional frequency parameter \bar{E}
r_1	normal distance from shell axis at initial edge
r_2	normal distance from shell axis at final edge
s	meridional shell coordinate
S_T	total meridional shell length
T	dimensional time
T_0	reference time
t	nondimensional time
$t_s, t_\theta, t_{s\theta}$	nondimensional membrane force series coefficients
t_T	nondimensional thermal membrane force series coefficients
U, V, W	displacements tangent to the meridian, tangent to the parallel circle and normal to the reference surface
u, v, w	nondimensional series coefficients of $U, V,$ and W
α^r	r^{th} iteration Rayleigh quotient eigenvalue, $\frac{-1}{(\omega^r T_0)^2}$
β	spectral shift point
γ	ρ'/ρ
Δ	distance between finite difference stations = $\frac{S_T}{(a(KMAX - 1))}$
δt	nondimensional time interval
ζ	shell coordinate perpendicular to reference surface
θ	shell circumferential coordinate

μ_i	nondimensional mass at i^{th} station $= \frac{a^2}{h_o^2 E_o^2 T_o^2} \int m \, d\zeta$
Ξ	nondimensional frequency parameter $= \omega r \sqrt{\frac{m(1-\nu^2)}{E_y}}$
ν	Poisson's ratio
ξ	nondimensional meridional coordinate, s/a
ρ	nondimensional normal distance to shell axis, r/a
$\sum_{i=m,j}^n$	summation over i from m to n in increments of j
σ_o	reference stress level
$\Phi, \Phi_s, \Phi_\theta$	reference surface rotations
$\phi, \phi_s, \phi_\theta$	nondimensional series coefficients for reference surface rotations
ω	natural frequency, radians per second
ω_s, ω_θ	nondimensional curvatures, $a/R_s, a/R_\theta$

MATRIX NOTATION

$A, B, \bar{B}, C, E, F, G, \bar{G}, H, J, P, DEE, DST$	4×4 matrices. Elements of the matrices are defined in Refs. 1 and 2.
$\bar{e}, \bar{f}, g, \bar{g}$	1×4 load vectors. Elements are defined in Refs. 1 and 2.
K	system stiffness matrix
ℓ	1×4 boundary condition vector
M	system mass matrix
W^r	system solution vector before eigenvalue extraction

z	1 x 4 solution vector
z^r	system solution vector after scaling and eigenvalue extraction.
$\bar{\Lambda}, \bar{\Omega}$	4 x 4 boundary condition matrices
$\bar{\mu}$	4 x 4 mass matrix
$[\]$	m x n matrix
$\{ \}$	column vector
$[_]$	row vector
$ \ $	absolute value of a scalar
$i=m(k)n$	i is stepped from m to n in increments of k

SUPERSCRIPTS

r	r^{th} iteration
T	transpose of a matrix or vector
$'$	(prime) partial differentiation in the meridional direction
-1	inverse of a matrix

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The author wishes to express his deepest gratitude to Dr. Robert E. Ball for his abiding faith, trust and understanding. Dr. Ball's insight and expert professional guidance were principle factors leading to the successful completion of this project.

I. INTRODUCTION

The free vibration analysis of shells of revolution is of major interest to the modern structural analyst since shells are used in the construction of everything from spacecraft to nuclear reactors. The modes of free vibration and the associated natural frequencies are of fundamental importance in understanding the dynamic behavior of shells.

This thesis is devoted to the incorporation of a free vibration analysis capability in the computer program known as SATANS (Static And Transient Aalysis, Nonlinear, Shells). The development of SATANS is described in Refs. 1, 2 and 3. In Section II of this thesis a brief description and history of the three versions of SATANS (known as SATANS, SATANS-I and SATANS-II) is presented. In Section III a brief explanation of the solution procedure used in SATANS is given. In Section IV, SATANS-III is developed. SATANS-III is a modification of SATANS-I incorporating the capability of a free vibration analysis. Major consideration was given to: (1) matching the vibration analysis procedure to the present program without the necessity of reformulating the original program, (2) maintaining the capability of having the shell material and geometric properties vary along the meridian, (3) having assurance of completely covering a frequency range in a given

Fourier harmonic. The selection of the inverse iteration procedure with spectral shifts meets these goals. In addition, a backup capability to handle unusual situations, such as a pair of complex conjugate eigenvalues, is included.

To illustrate the validity of SATANS-III the results of six analyses of shells of uniform thickness are compared with published results in Appendix B. In addition new results showing the analysis of a shell of linearly varying thickness is also given in Appendix B.

In Appendix A there is a short discussion of the difficulties of the present problem of a large, strongly banded, unsymmetric and occasionally singular stiffness matrix in conjunction with a singular mass matrix using other solution procedures.

The coding details for converting SATANS-I to SATANS-III are given in Appendix C. Appendices D through G constitute the user's manual for SATANS-III.

II. BRIEF DESCRIPTIONS OF SATANS: VERSIONS I, II AND III

SATANS [Refs. 1,2] existed in three forms prior to this work; the original code and two later modifications, SATANS-I and SATANS-II [Ref. 3].

A. THE ORIGINAL SATANS

SATANS [Refs. 1,2] is a digital computer program capable of performing geometrically nonlinear static and dynamic analyses of arbitrarily loaded shells of revolution. It is based upon a combination of Fourier series for the circumferential behavior and finite differences for the meridional analysis. The conditions that the program is based upon are:

1. The shell material is isotropic and Poisson's ratio is constant.
2. The elastic modulus may vary through the shell thickness.
3. All material and geometric properties are axisymmetric and may vary along the shell meridian.
4. The boundaries may be free, elastically restrained, fixed or closed (pole).
5. The loading may be any combination of a temperature distribution, pressure and edge load.
6. The applied pressure and temperature distributions, and initial conditions in the case of a dynamic analysis, must be symmetric about a reference meridional plane.

7. The maximum number of circumferential Fourier harmonics, MAXM, used to describe the loading and solution, is 10. The maximum number of meridional finite difference stations, KMAX, is 200. The limit on the product of KMAX and MAXM is 200.

SATANS requires approximately 155 K-bytes of core storage on an IBM 360/67 using the FORTRAN-H compiler with optimization level 2.

B. SATANS-I

SATANS-I, developed by Ryan [Ref. 3], consists mainly of a rearrangement of the original program and the addition of an equipment independent plotting package capable of handling 100 points. The rearrangement allows approximately 99% of the code to be pre-compiled and linked internally and stored on rapid-access secondary storage (disk, cell, tape, drum, etc). This stored package is called by a simple six card main program. The plotting package enables the user to obtain plots of all input and output variables on the high speed line printer. In addition, solutions at 36, vice 6 for SATANS, meridians may be printed and/or plotted. The restrictions on KMAX and MAXM are the same as for SATANS.

SATANS-I requires approximately 206 K-bytes of storage on an IBM 360/67 using the FORTRAN-H compiler with optimization level 2. Execution time is increased over that of SATANS by .01 seconds for each 100 point plot generated.

C. SATANS-II

SATANS-II, also developed by Ryan [Ref. 3], is an extensive expansion of SATANS-I. The following improvements were incorporated:

1. The ability to handle arbitrary initial imperfections in the shape of the shell was introduced.
2. The restriction on the applied loads, that they be symmetric about a reference meridian, was removed.
3. The maximum number of circumferential Fourier harmonics describing the completely general loads and the solution was increased to 13, and the maximum number of meridional stations was reduced to 100. The restriction on the product of KMAX and MAXM was raised to 951.

SATANS-II is a large program requiring 426 K-bytes of main core on an IBM 360/67 using the FORTRAN-H compiler with optimization level 2.

D. SATANS-III

SATANS-III is a modification of SATANS-I which incorporates the ability to perform a free vibration analysis of shells of revolution. SATANS-III operates under the same conditions as SATANS and SATANS-I. The procedure used to determine the modes and frequencies is inverse iteration with spectral shifts. One of three modes of operation is specified by the user. The three modes are:

1. Determination of the lowest frequency in a user specified circumferential harmonic.
2. Determination of the frequency closest to a user specified frequency in a user specified circumferential harmonic (supplied shift point mode).

3. Frequency range search (circumferential harmonic and end points of the frequency range specified by the user).

The assumptions made in determining the natural modes and frequencies are:

1. No loads of any type.
2. Small deflections and rotations.
3. All nonlinear effects are ignored.

SATANS-III requires 234 K-bytes of main core on an IBM 360/67 using the FORTRAN-H compiler with optimization level 2.

III. SOLUTION PROCEDURE

The solution procedure used in all of the versions of SATANS is based on Sanders' field equations [Ref. 4], with translational inertia terms added, assuming small strains and moderately small, or small, rotations. The basic method of solution was developed by Budiansky and Radkowski [Ref. 5] for the linear static case. A brief presentation of the method of solution is presented here for continuity. For a more detailed explanation refer to Refs. 1 and 2.

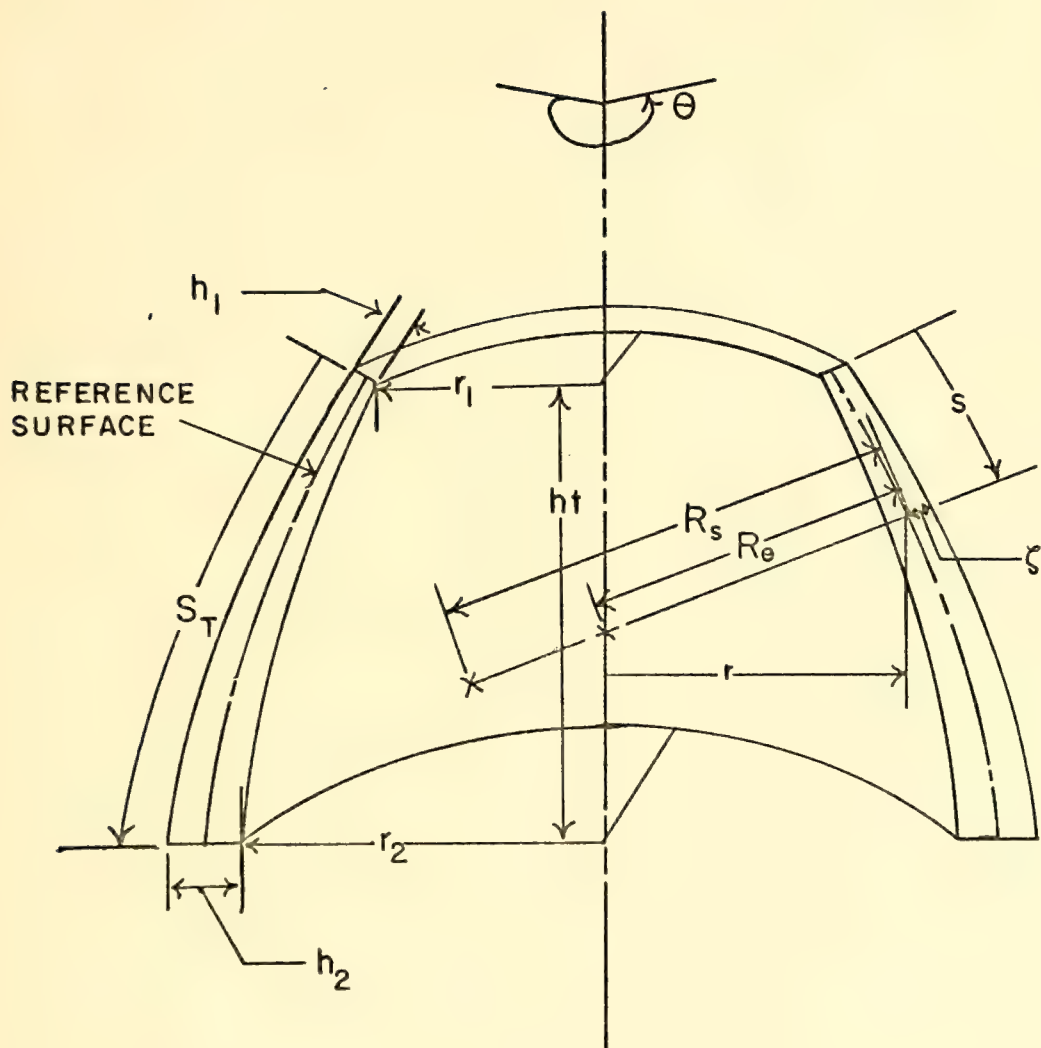
A. SHELL COORDINATE SYSTEM

Figure 1 depicts the orthogonal coordinate system used to describe the shell geometry. s is the distance along the meridian on the reference surface, θ is the circumferential angle, measured from some reference meridian, about the shell axis of revolution, and ζ is the coordinate through the thickness of the shell measured normal to the reference surface. The integral $\int E_y \zeta d\zeta = 0$ positions the reference surface, where E_y is Young's modulus.

Figure 2 depicts the positive directions for the displacements, rotations, forces, moments and loads.

B. METHOD OF SOLUTION

In the SATANS-I analysis the dependent variables in Sanders' nonlinear field equations are expanded into either a Fourier sine or cosine series in terms of $n\theta$, where n is



SHELL GEOMETRY AND COORDINATE SYSTEM

FIGURE 1

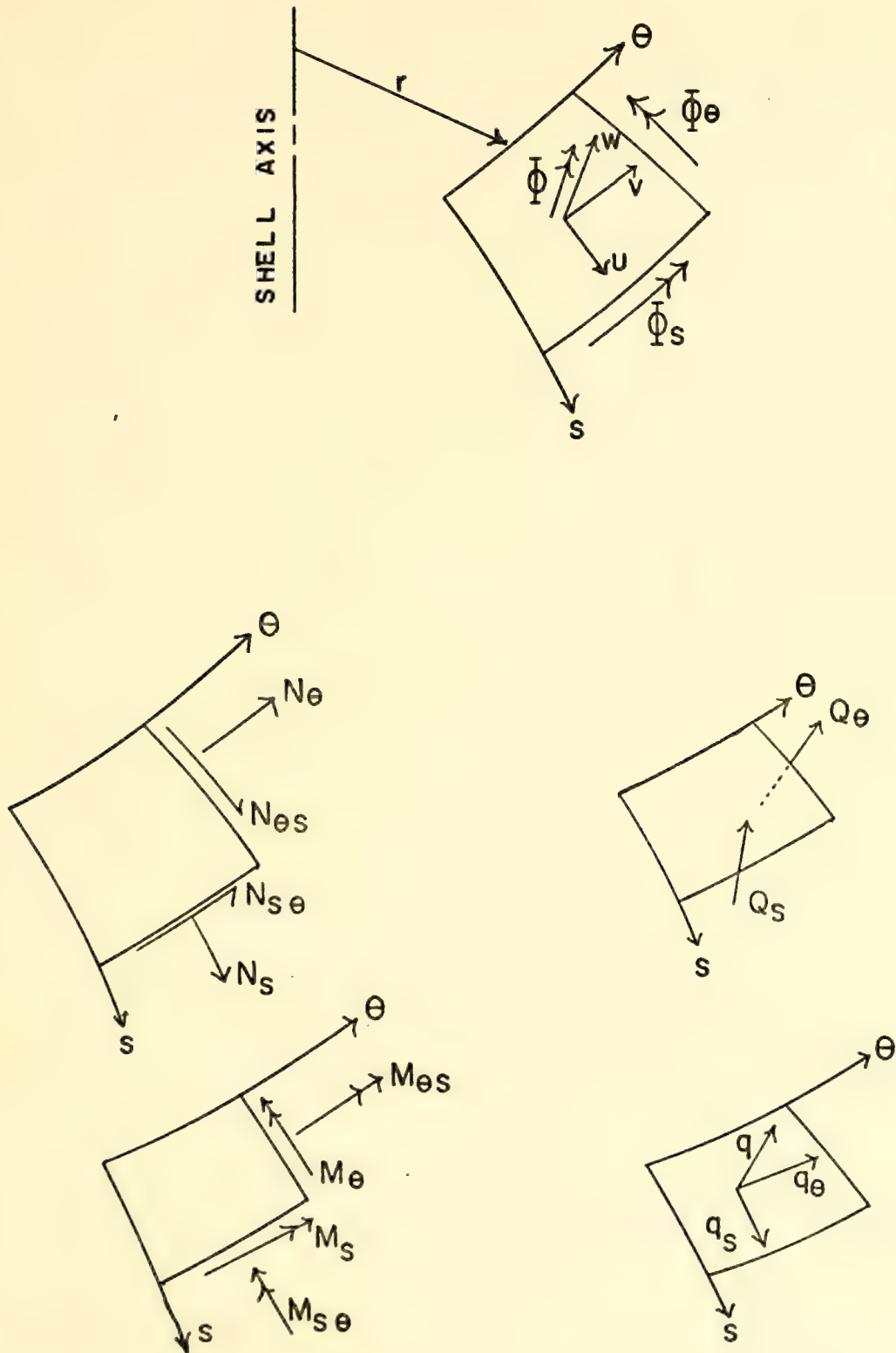


FIGURE 2 POSITIVE DIRECTIONS
FOR VARIABLES

the Fourier harmonic index. This results in a complete set of governing equations for each Fourier harmonic n . The nonlinear terms are products of two series. These products are expressed as a single series, the coefficients of which are also series. In order to uncouple the sets of equations the "pseudo load" approach is used, i.e. the nonlinear coupling terms are treated as known quantities and are included with the loads on the right side of the equations. Thus the left-hand side of the equations is linear and the sets are uncoupled.

Following the method suggested in Ref. 5 each set of uncoupled equations (one set for each value of n) is expressed as four second order differential equations. The independent variables are the series coefficients $u^{(n)}$, $v^{(n)}$, $w^{(n)}$ and $m_s^{(n)}$, representing the nondimensional meridional, circumferential and normal displacements and the meridional bending moment respectively. For convenience the superscript n will be dropped henceforth.

For each value of n , the set of four second order differential equations may be written in matrix notation as

$$E z'' + F z' + G z = \bar{e} + \bar{\mu} \frac{\partial^2 z}{\partial t^2} \quad (1)$$

where t is nondimensional time. Primes denote partial differentiation with respect to the nondimensional

meridional coordinate ξ . Vector \bar{e} contains the load and nonlinear terms.

The solution vector z is

$$z = \begin{Bmatrix} u \\ v \\ w \\ m_s \end{Bmatrix}$$

The mass matrix $\bar{\mu}$ is

$$\bar{\mu} = \mu \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix}$$

where the nondimensional mass μ is defined by the integral

$$\mu = \frac{a^2}{h_o E_o T_o^2} \int m d\xi \quad (2)$$

where m is the mass density of the shell material and a , h_o , E_o , and T_o are nondimensionalizing parameters. The elements of the 4×4 matrices E , F and G and the vector \bar{e} are given in Ref. 2.

Equations (1) are solved numerically using spatial and timewise differencing schemes. In both the static and dynamic analysis the first and second derivatives of z

are approximated using the central finite difference schemes

$$z_i' = (z_{i+1} - z_{i-1})/\Delta$$

$$z_i'' = (z_{i+1} - 2z_i + z_{i-1})/\Delta^2$$

where i denotes the station along the meridian and Δ is the uniform spacing between stations.

Houbolt's backward differencing scheme is used to approximate the second derivative with respect to time for the dynamic case.

$$\left. \frac{\partial^2 z}{\partial t^2} \right)_{i,j} = \frac{(2z_{i,j} - 5z_{i,j-1} + 4z_{i,j-2} - z_{i,j-3})}{(\delta t)^2}$$

The time step is denoted by j and δt is the nondimensional time interval.

The resulting set of four second order difference equations can be written in the matrix form

$$A_i z_{i+1,j} + \bar{B}_i z_{i,j} + C_i z_{i-1,j} = \bar{g}_{i,j} \quad (3)$$

for $i = 1, 2, 3, \dots, KMAX$. The 4×4 matrices A , \bar{B} and C and the vector \bar{g} are given by

$$A_i = (2E_i/\Delta) + F_i$$

$$\bar{B}_i = (-4E_i/\Delta) + 2\Delta\bar{G}_i$$

$$C_1 = (2E_1/\Delta) - F_1$$

$$\bar{G}_1 = G_1 - (2\bar{\mu}_1/(\delta t)^2)$$

$$\bar{g}_{1,j} = 2\Delta\bar{e}_{1,j} + \frac{2\Delta\bar{\mu}_1}{(\delta t)^2} (-5z_{1,j-1} + 4z_{1,j-2} - z_{1,j-3})$$

In the static analysis j denotes the load step and $\mu_1 = 0$.

The boundary conditions on z are entered on cards as the elements of two 4×4 matrices, $\bar{\Omega}$ and $\bar{\Lambda}$, and the column vector ℓ . The boundary conditions specify either the forces or the displacements at the shell boundary for all n considered.

The boundary condition matrix equation is

$$\bar{\Omega} \begin{Bmatrix} N_s \\ \hat{N}_s \\ N_{s\theta} \\ \hat{Q}_s \\ \phi_s \end{Bmatrix} + \bar{\Lambda} \begin{Bmatrix} U \\ V \\ W \\ M_s \end{Bmatrix} = \ell$$

where all terms are identified in Figure 2. The $\hat{}$ above \hat{N}_s and \hat{Q}_s denotes the effective edge variables. As an example, a clamped edge is specified by

$$\bar{\Omega} = \begin{bmatrix} \bar{0} & 0 & 0 & \bar{0} \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & \underline{1} \end{bmatrix} \quad \bar{\Lambda} = \begin{bmatrix} \bar{1} & 0 & 0 & \bar{0} \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ \underline{0} & 0 & 0 & \underline{0} \end{bmatrix}$$

and

$$\ell = \begin{Bmatrix} 0 \\ 0 \\ 0 \\ 0 \end{Bmatrix}$$

In order to convert the boundary conditions to finite difference form, the derivatives with respect to the meridional coordinate in the forces and rotations are replaced by the central finite difference schemes.

For each value of n the system of $KMAX + 2$ matrix equations may be written as

$$K Z = Y \quad (4)$$

Figure 3 depicts the elements of the K matrix and the Z and Y vectors.* The first and last rows of K are the boundary condition equations. The elements of the 4×4 matrices H and J and the four element vector \bar{F} are given

*There are $KMAX$ stations over the length of the shell where Equation (3) applies. The first and last stations are at the initial and final edges. This leads to $KMAX$ equilibrium equations. The boundary equations are also applied at the initial and final edges of the shell. Thus there are $KMAX + 2$ matrix equations. The application of Equation (1) and the boundary equations at the edges of the shell introduce one imaginary station off each edge of the shell. This results in $KMAX + 2$ unknown values of z . The vector Y consists of the $KMAX$ values of \bar{g} and the two terms at the initial and final positions representing the loads and the boundary condition values at the edges.

$$\begin{bmatrix}
 \frac{-\Omega_1 H_1^N}{2\Delta} & \Omega_1 J_1^N & \Lambda_1 & \frac{\Omega_1 H_1^N}{2\Delta} & & \\
 C_1^N & \bar{B}_1^N & A_1^N & & & \\
 & C_2^N & \bar{B}_2^N & A_2^N & & \\
 & & \circ & \circ & \circ & \\
 \hline
 & \circ & \circ & \circ & & \\
 & & C_K^N & \bar{B}_K^N & A_K^N & \\
 & \frac{-\Omega_K H_K^N}{2\Delta} & \Omega_K J_K^N & \Lambda_K & \frac{\Omega_K H_K^N}{2\Delta} &
 \end{bmatrix}
 \begin{bmatrix}
 Z_0^N \\
 Z_1^N \\
 Z_2^N \\
 \circ \\
 \circ \\
 Z_K^N \\
 Z_{K+1}^N
 \end{bmatrix}
 =
 \begin{bmatrix}
 l_1 - \Omega_1 \bar{f}_1^N \\
 \bar{g}_1^N \\
 \bar{g}_2^N \\
 \circ \\
 \circ \\
 \bar{g}_K^N \\
 l_K - \Omega_K \bar{f}_K^N
 \end{bmatrix}$$

$\begin{matrix} K & Z & Y \end{matrix}$

FIGURE 3 SYSTEM STIFFNESS
MATRIX, LOAD AND SOLUTION VECTORS

in Ref. 2. The system is tridiagonal in the matrix sense and Potters' form of Gaussian elimination is used to solve for the $z_{i,j}$. For the forward pass

$$x_{i,j} = DEE_i \bar{g}_{i,j} - DST_i x_{i-1,j} .$$

For the backward pass

$$z_{i,j} = -P_i z_{i+1,j} + x_{i,j} .$$

The 4×4 matrices P_i , DEE_i and DST_i are independent of the load and solution and are determined only once. They are given by

$$DEE_i = (\bar{B}_i - C_i P_{i-1})^{-1}$$

$$P_i = DEE_i A_i$$

$$DST_i = DEE_i C_i$$

The initial value of $x_{1,j}$ on the forward pass and the initial value of $z_{k+1,j}$ on the backward pass are specially determined according to the boundary conditions. Special procedures are also invoked in the case of a shell with an initial and/or final pole [Ref. 2].

C. STATIC ANALYSIS

Figure 4 illustrates a typical load history and solution path for a static analysis. A solution to a monotonically increasing load is obtained at each load step in an iterative process. The load is incremented by DELOAD each step. A solution is obtained for each Fourier harmonic index considered. The pseudo loads are recomputed each iteration at each load step. The solution at each iteration is tested for convergence. There is no solution to estimate the pseudo loads on the first load step and the result after the first iteration is a linear solution. If convergence occurs, the load is incremented by the amount DELOAD, an estimate of the solution is made by a linear extrapolation of the last two solutions, and the iteration process is repeated.

If convergence is not obtained in a specified number of iterations, ITRMAX, the total load, ALOAD, is decremented by one DELOAD. DELOAD is reduced to 20% of its previous value and becomes the new incremental load. The iteration process is then repeated. The program terminates when DELOAD has been reduced to 20% of its previous value a specified number of times (LCHMAX), or when a specified number of load steps has been taken.

Because of the pseudo load approach, failure to converge to a solution may be due to either of two types of nonlinear behavior illustrated in Figure 4. Curve A experiences a

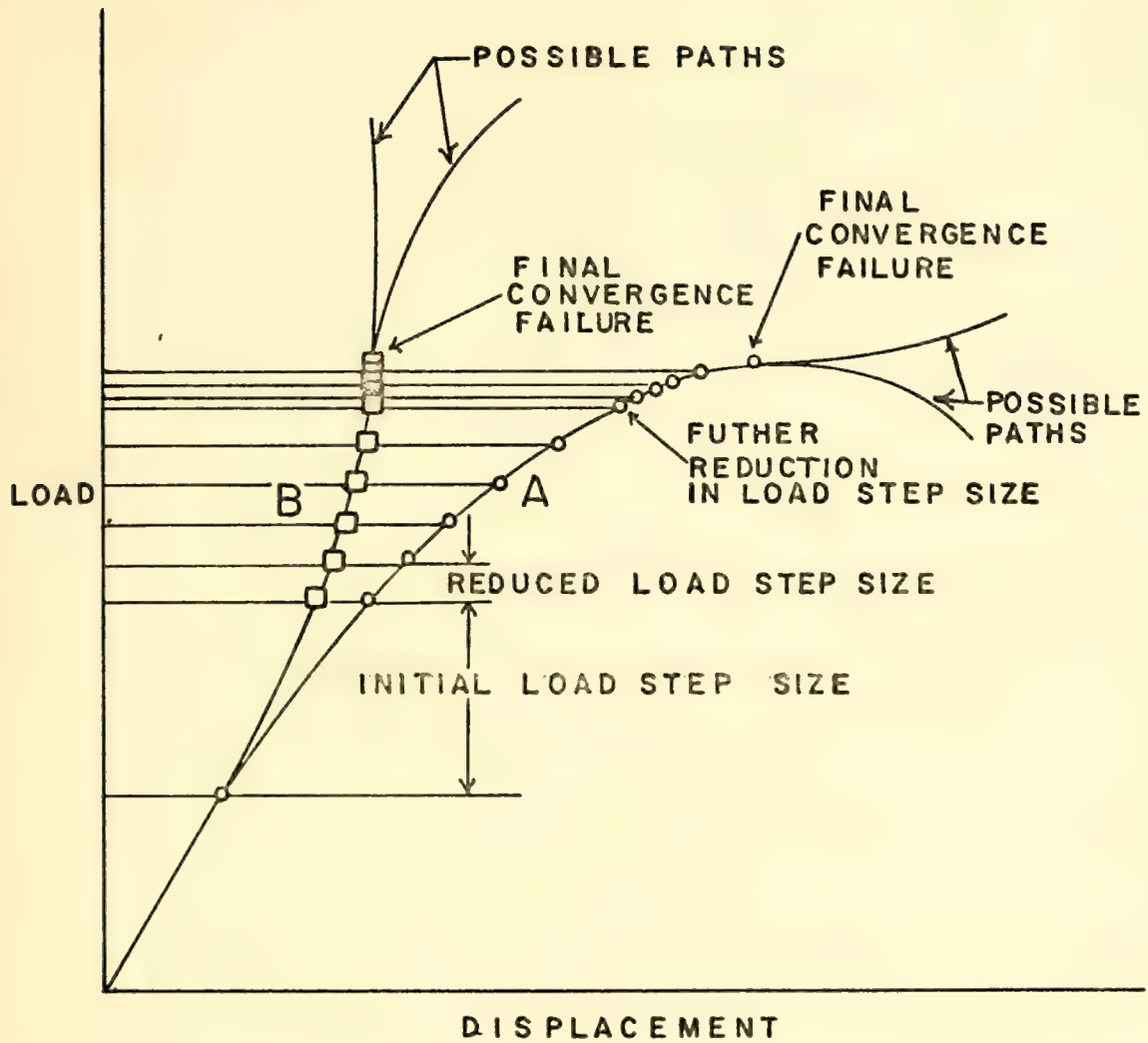


FIGURE 4 NONLINEAR BEHAVIOR
AFFECTING CONVERGENCE

maximum or inflection point, typical of a softening non-linearity, causing convergence failure. Curve B experiences an ever increasing slope, typical of a stiffening nonlinearity, causing convergence failure.

D. DYNAMIC ANALYSIS

The applied load in the dynamic analysis is a function of the time step j . DELOAD is the incremental time δt . Initial conditions on z and $\partial z / \partial t$ are supplied in a user prepared subroutine, INITL. The procedure is essentially the same as the static analysis except the load step becomes the time step. The program terminates under one of two conditions. Either convergence is not obtained in the specified number of iterations, ITRMAX, or the maximum number of time increments, LSMAX, has been reached.

IV. DEVELOPMENT OF SATANS-III

A. FREE VIBRATION EQUATIONS

Recall the set of four second order differential equations written in Equation (1) was

$$E z'' + F z' + G z = \bar{e} + \bar{\mu} \frac{\partial^2 z}{\partial t^2} \quad (1)$$

In the free vibration analysis the nonlinear terms are ignored and no loading exists. Hence the vector \bar{e} does not exist under these conditions. Assuming harmonic motion, the solution vector $z(\xi, T)$ takes the form $e^{i\omega t T_0} z(\xi)$ where T_0 is a time constant and ω is the natural frequency in radians per second. Therefore Equation (1) simplifies to

$$E z'' + F z' + G z = -\omega^2 T_0^2 \bar{\mu} z \quad (5)$$

Using the same spatial finite differencing schemes used in SATANS-I, Equation (5) becomes

$$A_1 z_{i+1} + \bar{B}_1 z_i + C_1 z_{i-1} = -\omega^2 T_0^2 \bar{\mu}_1 2\Delta z_i \quad (6)$$

for $i = 1, 2, \dots, KMAX$. The elements of the matrices A , \bar{B} , and C are the same as those for a static analysis.

Equation (6) can be written in the matrix form of a standard

eigenvalue problem

$$K Z = -\omega^2 T_o^2 M Z \quad (7)$$

where the K matrix is the same as the one shown in Figure 3. The mass matrix M will be described in the following section.

B. CHARACTERISTICS OF THE PROBLEM

There are three main areas to consider when incorporating a free vibration analysis capability in an existing program. Consideration must be given to the form of the desired results and the expected benefits of the vibration analysis. Consideration must also be given to both compatibility with the existing code and the nature of the problem itself.

1. Desired Results

Generally, only the lower frequencies in each Fourier harmonic are sought. The lowest 10 is a common figure. For example, Kalnins, in Reference 6, points out that there is a practical limit to which a linear theory correctly approximates the higher frequencies of a real shell. The mode shapes are also usually desired. In certain applications only a specific range of frequencies is of interest. Some assurance of finding all the frequencies in that range is desired.

2. Nature of the Problem

The mass matrix M is diagonal and singular and is of the form

$$M = 2\Delta$$

$$\begin{bmatrix} 0 & & & & & & & \\ & \bar{\mu}_1 & & & & & & \\ & & \cdot & & & & & \\ & & & \cdot & & & & \\ & & & & \bar{\mu}_{i-1} & & & \\ & & & & & \bar{\mu}_i & & \\ & & & & & & \bar{\mu}_{i+1} & \\ & & & & & & & \cdot \\ & & & & & & & \cdot \\ & & & & & & & \bar{\mu}_{KMAX} \\ & & & & & & & & 0 \end{bmatrix}$$

When the meridional, circumferential and radial translational inertial forces are all considered

$$\bar{\mu}_i = \mu_i \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix}$$

If only the translational inertial forces in the radial direction are considered

$$\bar{\mu}_i = \mu_i \begin{bmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix}$$

The stiffness matrix, K , Figure 3, is unsymmetric and singular in some cases due to the boundary conditions. K has a bandwidth of 15, or 3 if considered in the matrix sense. When the number of meridional stations is the maximum of 200, K has an order of 808. If K were stored in the banded form taking no account of the zeroes in the band, 48 K-bytes of IBM 360/67 main core are required. Potters' elimination scheme requires only 38.4 K-bytes of main core. Because K is unsymmetric, there is no absolute guarantee, from a mathematical viewpoint, that the eigenvalues and eigenvectors are real. Some capability in this area is sought, both as a trouble shooting aid and as a complex root solver.

Ill-conditioning in the solution may result from several causes. Small separations between the eigenvalues, numerical conditioning of the K matrix and the loss of significance are some reasons that make eigenvalue/eigenvector determination difficult. Thus it is desirable to have a capability to handle such cases, but not to have to pay the price of determining every eigenvalue and eigenvector of the total system.

C. SOLUTION TO THE EIGENVALUE PROBLEM

The method of solution to the eigenvalue problem selected for inclusion in SATANS-I is inverse iteration with spectral shifts. This scheme melds with the existing code extremely well. In addition, a capability to handle special ill-

conditioning problems and complex roots has been included. A brief discussion of other possible solutions to the real unsymmetric eigenvalue problem appears in Appendix A.

The inverse iteration procedure is eminently suited for accurate determination of eigenvalues and eigenvectors [Refs. 7 and 8]. The amount of work involved is directly proportional to the number and accuracy of the eigenvalues and eigenvectors sought. The coding is simple and requires a very small increase in core. Lastly, the eigenvectors and eigenvalues are determined simultaneously. The basic scheme is well known [Refs. 7-14]. However, the scheme used in SATANS-III is slightly different and is explained below.

The basic iterative procedure is obtained by rewriting Equation (7) in the form

$$[K - \beta M]W^{r+1} = M Z^r$$

where

$$W^{r+1} = \alpha^{r+1} Z^{r+1}$$

and

$$\alpha = \frac{-1}{(\omega^2 T_o^2) + \beta}$$

where r denotes the r th iteration and β is the spectral shift value.

a. The vector Z^r is assumed for the first iteration and afterward is computed using W^r . Prior to solving for W^{r+1} the mass matrix M must be premultiplied through the vector Z^r . This consists merely of multiplying the diagonal of $2\Delta\bar{\mu}_1$ through each z_1^r . Since the mass may vary along the meridian removal of this variable from the right hand side of the equation was desirable. This was accomplished by dividing each element of the A_1 , \bar{B}_1 and C_1 matrices by $2\Delta\mu_1$ at the time of their computation. These additional computations are only performed in the vibration analysis state of the program. The net result of this procedure is that the diagonal of $\bar{\mu}_1$ merely consists of ones and zeroes.

b. W^{r+1} is solved for by Potters' elimination scheme as in the original SATANS-I program.

c. α^{r+1} is determined from the "Rayleigh quotient type" computation

$$\alpha^{r+1} = \frac{(Z^r)^T W^{r+1}}{(Z^r)^T Z^r} \quad (8)$$

which may be thought of as resulting from

$$\frac{(Z^r)^T ([K - \beta M]^{-1} M Z^r)}{(Z^r)^T Z^r}$$

realizing, of course, that this is not the manner in which the computations are performed. In the limit, as r approaches infinity, Z^{r+1} approaches Z^r , when Z^r is real. This

computation also determines the sign of α^{r+1} . The vector z^{r+1} is scaled such that the largest element before each iteration is unity. It sometimes happens in the first few iterations that α^{r+1} is smaller than the largest element of the vector, and scaling by the largest element prevents vector element build-up. In the limit, as r approaches infinity, α^{r+1} becomes equal to the largest element. Hence, if the convergence test is failed, steps a through c are repeated with

$$z^{r+1} = \frac{w^{r+1}}{\max (w_i^{r+1})}$$

d. The primary convergence test is performed on α^{r+1} . The test is

$$\left| \frac{|\alpha^{r+1}| - |\alpha^r|}{\alpha^{r+1}} \right| = < \text{EPSVIB}.$$

The absolute value of α is used because due to the spectral shifts α may be negative. In that case α changes sign each iteration but converges in absolute value. A secondary convergence test is optional and is performed on the vector elements themselves. The vector test is more stringent than the primary convergence test and increases the computation time. The vector test consists of comparing the difference between two successive iterations with the maximum values of u , v , w and m_s , times EPSVEC, a convergence criterion, for the last iteration.

Recall that

$$Z = \begin{Bmatrix} \cdot \\ \cdot \\ \cdot \\ z_{i-1} \\ z_i \\ z_{i+1} \\ \cdot \\ \cdot \\ \cdot \end{Bmatrix} \quad \text{where } i \text{ denotes the station,}$$

and

$$z_i = \begin{Bmatrix} u_i \\ v_i \\ w_i \\ m_{s_i} \end{Bmatrix} = z_{i,k} \quad \text{where } k = 1(1)4$$

such that $z_{i,1} = u$, $z_{i,2} = v_i$... etc. for each station i . The vector test may then be stated as follows

$$z_{i,k}^{r+1} - z_{i,k}^r = < \max(z_{i,k}^{r+1}) \times \text{EPSVEC}$$

for $i = 1(1)\text{KMAX2}$

$k = 1(1)4$.

EPSVEC = EPSVIB unless otherwise specified on input.

e. When convergence has occurred one more iteration is performed and the vector is scaled using the value of α^{r+1} given by Equation (8). This yields an indication

of the quality of the solution by inspecting the largest element of the vector, which should be essentially 1.0.

f. The eigenvalue is obtained by taking the reciprocal of α^{r+1} and subtracting the spectral shift value, β .

$$(\omega^2 T_o^2)^{r+1} = \frac{-1}{(\alpha^{r+1})} - \beta$$

In the program the FORTRAN variables are

```
VREAL = (ONEDO/SCALEW) + ASHIFT  
AREAL = SNGL(VREAL)
```

where AREAL and ASHIFT are single precision variables and VREAL, ONEDO and SCALEW are double precision variables.

g. If the program is unable to determine a real eigenvalue in the specified number of iterations (ITRMAX), control is passed to a backup routine, ITCPLX. This routine, which is described in Appendix C, Part Three, was developed to handle special ill-conditioning and non-convergence problems. The results of the routine are the two closest frequencies, real or complex, to the shift point. In addition, diagnostic messages are provided to aid in solving the problem at hand. These additional computations are only performed when the primary iteration routine fails to converge to a solution.

Some of the advantages of the selected scheme have been mentioned in the preceding paragraphs. Another is that iteration provides the ability to determine the frequencies

and mode shapes to almost any precision desired. The iterated vector is computed in double precision in order to handle cases of ill-conditioning and weakly determined frequencies, [Ref. 7]. This adds only slightly to the computation time and has paid off in the ease with which difficult frequencies are determined. Because the mode shapes are also determined, they require no additional calculations and yield an immediate answer to the question of which mode has actually been determined. The answer to this question is not always known in other methods [Ref. 15].

The iteration method avoids all manner of mathematical and numerical problems by actually performing the calculations of the solution procedure. The fact that the K matrix is unsymmetric and that both the K and M matrices are singular has no special impact on the solution procedure. There is no need to reformulate the problem or the program code, a major consideration in the present situation.

D. TESTING OF SATANS-III

The program has undergone considerable testing. Because of the size of SATANS-III, the inverse iteration scheme was tested in prototype form first. This included quite a bit of testing of the backup capability planned into the program in addition to the primary scheme [Refs. 7,8,16 and 17]. Appendix B tabulates six test cases for SATANS-III and compares them with published results. The agreement is excellent.

The test cases consist of determining the minimum frequencies of the lower circumferential harmonic (wave) numbers of three cones, a regular right circular cylindrical shell and a shell of positive gaussian curvature. There is also a determination of the lower spectrum of frequencies in each circumferential wave number for the right circular cylindrical shell. Lastly, there is an analysis of the effect of a linearly varying thickness on the minimum frequencies of the lower circumferential wave numbers of the right circular cylindrical shell.

V. CONCLUSIONS

Application of SATANS-III to many test cases has demonstrated that the inverse iteration technique with spectral shifts is a rapid, accurate and effective method for determining the natural modes and frequencies of the free vibration of shells of revolution. The simultaneous determination of the modes and frequencies provides an opportunity for determining if a mode has been missed, and the supplied shift point operation provides an easy method of determining the missed mode. The fact that sweeping of the vectors was not used in determining the higher frequency modes posed no special problem. In addition, not using vector sweeping allows the use of fewer mass points and more rapid calculation of some frequencies and modes. Dividing the variable mass into the component matrices of the K matrix proved to be an effective method of eliminating this variable from the right side of the vibration equations.

A study of the effect of a linearly varying thickness on the minimum frequencies of a circular cylindrical shell showed that as the percentage thickness of the lower edge over the upper edge increases the cylinder begins to exhibit behavior somewhat similar to that of a cone. The minimum frequency begins to appear in lower circumferential harmonics and the axial half wave number begins to rise.

The program experiences some difficulty with extremely thin shells, corners and very small radii of curvature. This might be alleviated by using a finer grid (more grid points) or as a further modification the incorporation of a variable grid capability.

Another further modification needed is the addition of preloads to the shell. Many of the methods used to determine the modes and frequencies of preloaded shells require accurate initial estimates of the solution to start the procedure. SATANS-III provides these estimates. It is felt that a preload capability can be incorporated into SATANS-III and still keep the program an in-core routine requiring only two core boxes.

APPENDIX A

OTHER SOLUTION METHODS

There are primarily two approaches to the unsymmetric matrix eigenvalue problem. The transformation methods are characterized by the operations, finite or infinite in number, being performed on the matrix.* The iterative methods are characterized by the operations being performed on the solution vector rather than the matrix.

There are basically four transformation methods capable of handling a real, unsymmetric matrix eigenvalue problem. Lanczos' method, the QR and the LR algorithms, are well known [Refs. 7-12]. The QZ algorithm recently developed at Stanford University [Ref. 18] is based on the QR algorithm and can handle a problem in the form $Ax = \lambda Bx$ with A and B unsymmetric and complex. They all suffer, with respect to the present problem, from the same deficiencies. For example, the greatest portion of the computation time is spent before the first eigenvalue is extracted and they require that the order and size of the matrix be the same. For the case of an unsymmetric banded matrix enough core storage must be set aside for at least half the matrix.

*The general problem $Ax = \lambda Bx$ may also be thought of as $Kz = \lambda z$. In the present problem, the full matrix form of K would require 2,560 K-bytes of core storage on an IBM 360/37.

Lanzcos' method for the unsymmetric case requires core storage for the generation of two sets of biorthogonal vectors in addition to the matrix itself. It is believed that this method would require the greatest storage and computation time. The LR algorithm without interchanges maintains the banded form but suffers from excessive computation time for closely spaced eigenvalues. In addition, the LR algorithm may be numerically unstable in some cases.

By far the most popular and successful transformation method in general use is the QR (and now also the QZ) algorithm. It is stable, fast, accurate and can handle complex numbers. The IMSL group [Ref. 19] is dedicated to speed and accuracy, and virtually all of their routines are variations of the QR and QZ algorithms. The QR algorithm without reduction to Hessenberg form requires a comparatively large number of calculations. Consequently the matrices are generally reduced to Hessenberg form which considerably reduces the computation time required to reach convergence. Again the main objections with respect to the problem considered here is computation time or core storage. Wilkinson [Ref. 7] states "If the LR algorithm with interchanges (which is stable) or the QR algorithm is used the band form above the main diagonal is gradually destroyed." This is also true of any method that employs a transformation to Hessenberg form. See Figure 5.

Another disadvantage of the transformation methods is the necessity of determining the eigenvectors in a separate operation from the natural frequencies.

REDUCTION OF A MATRIX TO HESSENBERG FORM

GIVENS' METHOD

INPUT MATRIX

3.000	2.000	1.000	0.0	0.0	0.0	0.0	0.0
4.000	3.000	2.000	1.000	0.0	0.0	0.0	0.0
5.000	4.000	3.000	2.000	1.000	0.0	0.0	0.0
0.0	5.000	4.000	3.000	2.000	1.000	0.0	0.0
0.0	0.0	5.000	4.000	3.000	2.000	1.000	0.0
0.0	0.0	0.0	5.000	4.000	3.000	2.000	1.000
0.0	0.0	0.0	0.0	5.000	4.000	3.000	2.000
0.0	0.0	0.0	0.0	0.0	5.000	4.000	3.000

MAJOR STEP NUMBER 1

3.000	2.030	-0.937	0.0	0.0	0.0	0.0	0.0
6.403	5.927	-1.659	0.781	0.0	0.0	0.0	0.0
0.0	0.341	-0.073	0.625	0.0	0.0	0.0	0.0
0.0	6.247	-1.406	2.000	1.000	0.0	0.0	0.0
0.0	3.504	-3.123	3.000	2.000	1.000	0.0	0.0
0.0	0.0	0.0	4.000	3.000	2.000	1.000	0.0
0.0	0.0	0.0	5.000	4.000	3.000	2.000	1.000
0.0	0.0	0.0	0.0	5.000	4.000	3.000	2.000

MAJOR STEP NUMBER 2

3.000	2.030	-0.043	0.027	0.0	0.0	0.0	0.0
6.403	5.927	-2.189	-0.445	0.0	0.0	0.0	0.0
0.0	7.375	5.740	-0.321	1.906	0.529	0.0	0.0
0.0	0.0	-0.537	-0.271	0.055	0.848	0.0	0.0
0.0	0.0	-2.455	-0.201	1.168	2.000	1.000	0.0
0.0	0.0	6.353	0.750	3.000	3.000	2.000	1.000
0.0	0.0	2.647	4.242	4.000	4.000	3.000	2.000
0.0	0.0	0.0	0.0	5.000	4.000	3.000	2.000

FIGURE 5

MAJOR STEP NUMBER 3

3.000	2.030	-0.043	-0.059	-0.920	0.161	0.023	0.0
6.403	5.927	-2.189	-0.279	-1.639	0.757	0.108	0.0
0.0	7.375	5.740	-1.967	-0.137	0.367	-0.194	0.0
0.0	0.0	7.327	5.790	0.369	-0.605	-0.084	1.590
0.0	0.0	0.0	-0.296	-0.607	-0.200	-0.080	0.368
0.0	0.0	0.0	-0.181	-3.050	-0.602	0.033	1.529
0.0	0.0	0.0	-4.163	-1.115	-2.320	0.548	3.000
0.0	0.0	0.0	5.781	0.0	1.839	2.050	

MAJOR STEP NUMBER 4

3.000	2.030	-0.043	-0.059	0.047	-0.619	5.698	-0.066
6.403	5.927	-2.189	-0.279	0.112	-1.503	-0.988	-0.155
0.0	7.375	5.740	-1.967	-0.128	-0.242	-0.088	0.178
0.0	0.0	7.327	5.790	0.369	-0.709	0.033	0.312
0.0	0.0	0.0	7.132	-1.864	-0.397	-0.233	0.063
0.0	0.0	0.0	0.0	-0.374	-1.720	-1.611	-0.018
0.0	0.0	0.0	0.0	0.767	-1.108	-1.250	-0.148
0.0	0.0	0.0	0.0	0.0	-2.127		

MAJOR STEP NUMBER 5

3.000	2.030	-0.043	-0.059	0.047	-0.066	0.930	-0.019
6.403	5.927	-2.189	-0.279	0.112	-0.108	1.747	-0.441
0.0	7.375	5.740	-1.967	-0.128	0.356	-0.049	-0.214
0.0	0.0	7.327	5.790	0.369	-0.208	-0.547	-0.413
0.0	0.0	0.0	7.132	-1.864	-0.333	-0.441	0.098
0.0	0.0	0.0	0.0	0.921	1.237	1.595	-2.040
0.0	0.0	0.0	0.0	0.0	0.227	0.034	-1.639
0.0	0.0	0.0	0.0	0.0	0.936	-2.757	

MAJOR STEP NUMBER 6

3.000	2.030	-0.043	-0.059	0.047	-0.066	0.200	-0.909
6.403	5.927	-2.189	-0.279	0.112	-0.108	-0.018	-1.802
0.0	7.375	5.740	-1.967	-0.128	0.356	-0.220	-0.003
0.0	0.0	7.327	5.790	0.369	-0.208	0.273	0.629
0.0	0.0	0.0	7.132	-1.864	-0.333	0.165	-0.414
0.0	0.0	0.0	0.0	0.921	1.237	-1.693	-2.044
0.0	0.0	0.0	0.0	0.0	0.227	-2.270	-2.099
0.0	0.0	0.0	0.0	0.0	0.936	-0.156	0.664

FIGURE 5 CONTINUED

An approach taken by some [Ref. 20] is to cast the problem into a form that is easily handled by one of the more popular methods. The difficulty here lies in that many of the operations depend on at least one of the matrices in the general problem $Ax = \lambda Bx$ being nonsingular in all circumstances. This was not the case with the present problem. It was felt that the amount of work involved in either reformulating the problem or reducing the matrices to a form that could be transformed easily involved too much computational effort.

A method classed as iterative, but one that does not operate on the vector, is that of evaluating a determinant. This has been applied to the present problem by other researchers [Refs. 6, 21, 22]. One of the difficulties with this method is that one or two initial guesses at the eigenvalue must be made to start the process. The better the guess the faster the convergence. Another is that, unlike the inverse iteration process, there is no inherent determination of the eigenvalue spectrum under consideration. Having no a priori knowledge of the solution to a particular problem it is possible to miss a mode and not realize it [Ref. 15]. This method also requires separate determination of the eigenvectors.

When the inverse iteration procedure was chosen as the solution procedure it was also decided that orthogonality and sweeping of the vectors would not be employed. Because the K matrix is never determined explicitly, the use of a

sweeping matrix was not considered. Sweeping, if it would be employed, would have to operate solely on the vectors [Ref. 23]. Because the K matrix is unsymmetric the right hand vectors (mode shapes) are not orthogonal through K or M, although they are independent. The vectors that are orthogonal are the right and left hand vectors. If modal sweeping is used a total of 6 K-bytes of main core is required for each vector swept (3 K-bytes per vector; two vectors per mode). An increase in computation time also results from the sweeping operation.

Orthogonality relationships for the mode shapes can be developed in the continuous theory, but if an unsymmetric K matrix results from the implementation of the theory then the right hand vectors are not, in fact, orthogonal. In some situations the right hand vectors have been treated as if they were orthogonal when they are not [Refs. 13, 24]. The critical factor, in this case, is the number of mass points chosen to approximate the continuous system. As the number of mass points increases the approximation to the correct mode shapes (which are orthogonal) becomes more accurate. For this condition the sweeping operation becomes effective, but the computation time also increases. With a few mass points the eigenvalues may be accurately determined and the computation time reduced considerably. However, the sweeping operation then serves only to introduce unwanted errors. It was felt that to effectively employ sweeping would result in a large computation time and core requirement

that could not be justified by the results. In addition, in some of the cases investigated using sweeping of the right hand vectors as if they were orthogonal, there seemed to be no immediately apparent correlation between an increase in the number of mass points and the resultant increase in the quality of the pseudo orthogonality of the right hand vectors.

APPENDIX B

NATURAL FREQUENCIES OF SOME SELECTED SHELLS

TABLE I

MINIMUM NATURAL FREQUENCIES (Hz) OF A
THIN CIRCULAR CYLINDRICAL SHELL₍₁₎

<u>Circumferential Wave Number, n</u>	<u>Ref. 25</u>	<u>Ref. 26</u>	<u>SATANS-III</u>
1		1446.0	1446.2
2	633.5	634.5	635.5
3	326.7	327.5	328.2
4	202.3	203.8	203.7
5	159.9	162.6	160.9
6	168.0	171.6	168.7
7	206.0	210.1	206.5
8	261.0	265.4	261.6
9		331.9	328.0
10	403.4	408.0	404.1
11		492.8	488.8
12	581.1	585.5	582.0
13		687.3	683.4
14	791.8	796.9	793.0
15		914.7	911.0
16		1041.0	1036.9
17		1175.0	1171.1
18		1317.0	1313.5
19		1467.0	1463.9
20		1626.0	1622.5

(1) Configuration 1, Table VI.

TABLE II
NATURAL FREQUENCIES (Hz) OF A THIN CIRCULAR CYLINDRICAL SHELL⁽¹⁾

Circum. Wave Number, n	Axial Half-Wave Number, m											
	m = 1			m = 2			m = 3			m = 4		
	A	B	C	A	B	C	A	B	C	A	B	C
4	202.3	203.8	203.7	696.1	697.5	698.0						
5	159.9	162.6	160.9	483.0	484.6	484.6	960.6	962.5	963.3			
6	168.0	171.6	168.7	370.5	372.7	371.9	724.0	725.9	726.5			
7	206.0	210.1	206.5	325.1	328.1	326.3	580.8	583.2	583.2			
8	261.0	265.4	261.6	329.2	332.9	330.2	506.1	509.0	508.3	768.3	771.0	771.2
10	403.4	408.0	404.1	429.2	433.7	430.1	506.6	510.7	508.4	649.9	653.6	653.1
12	581.1	585.9	582.0	594.9	599.7	596.0	632.3	637.1	633.9	706.4	711.1	709.0
14	791.8	796.9	793.0	801.8	806.9	803.0	824.7	829.9	826.2	867.6	872.7	869.7

(1) Configuration 1, Table VI.
(A) Reference 25
(B) Reference 26
(C) SATANS-III

TABLE III

MINIMUM NATURAL FREQUENCIES (Hz) OF A FREELY
SUPPORTED CIRCULAR CYLINDRICAL SHELL₍₁₎

Circum. Wave Number, n	With Inplane Inertia DIAG = (1,1,1,0)		Without Inplane Inertia DIAG = (0,0,1,0)	
	f	Ξ (2)	f	Ξ
1	125.613	0.372	168.177	0.498
2	61.26	.182	69.24	.285
3	33.11	.0981	35.09	.104
4	19.92	.0590	20.58	.0610
5	13.62	.0403	13.90	.0412
6	10.07	.0298	10.21	.0303
7	8.494	.0252	8.583	.0254
8	8.285	.0245	8.351	.0247
9	9.057	.0268	9.114	.0270
10	10.33	.0306	10.38	.0308
11	12.08	.0358	12.13	.0359
12	14.24	.0422	14.29	.0423
13	16.58	.0491	16.63	.0493
14	19.16	.0568	19.21	.0569
15	21.96	.0651	22.01	.0652
16	24.94	.0739	24.99	.0740
18	31.56	.0935	31.61	.0936
20	38.95	.115	39.00	.115
22	47.14	.140	47.19	.140
24	56.12	.166	56.10	.166
26	65.87	.195	65.91	.195
28	76.40	.226	76.41	.226

(1) Configuration 2, Table VI.

(2) Dimensionless Frequency Parameter $\Xi = \omega \bar{r} \sqrt{\frac{m(1-\nu^2)}{E_y}}$

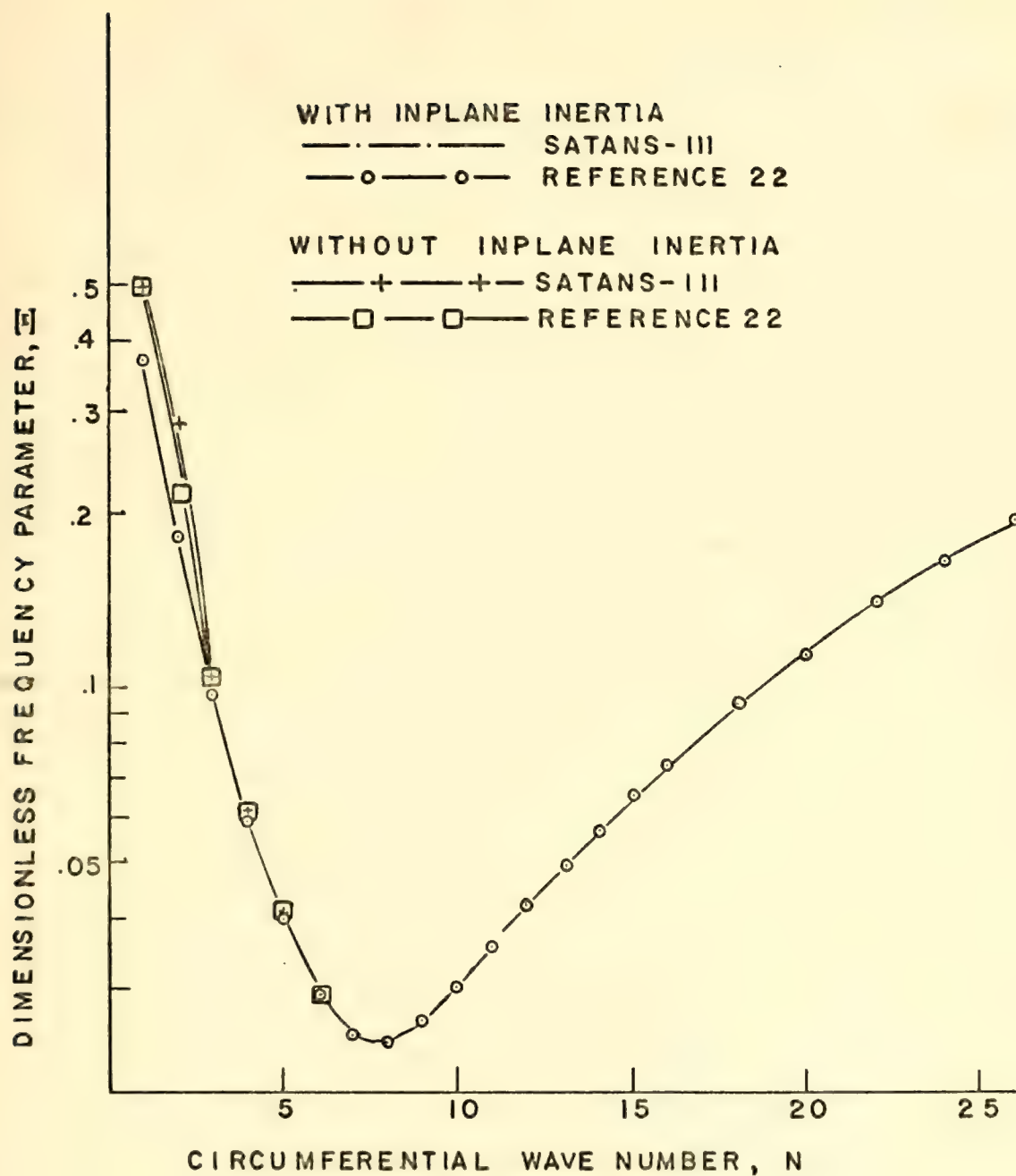


FIGURE 6 MINIMUM NATURAL FREQUENCIES OF A FREELY SUPPORTED CIRCULAR CYLINDRICAL SHELL CONFIGURATION 2, TABLE VI

TABLE IV
 MINIMUM NATURAL FREQUENCIES OF A
 SHELL OF POSITIVE GAUSSIAN CURVATURE₍₁₎

Dimensionless Frequency Parameter

$$\Xi = \omega \bar{r} \sqrt{\frac{m(1-\nu^2)}{E_y}}$$

<u>Circumferential Wave Number, n</u>	<u>Ref. 27</u>	<u>Ref. 22</u>	<u>SATANS-III</u>
1	0.411	0.412	0.411
2	.360	.362	.360
3	.340	.340	.340
4	.331	.331	.331
5	.327	.327	.327
6	.324	.324	.324
7	.323	.322	.323
8	.322	.321	.322
9	.321	.321	.321
10	.321	.321	.321

(1) Configuration 3, Table VI.

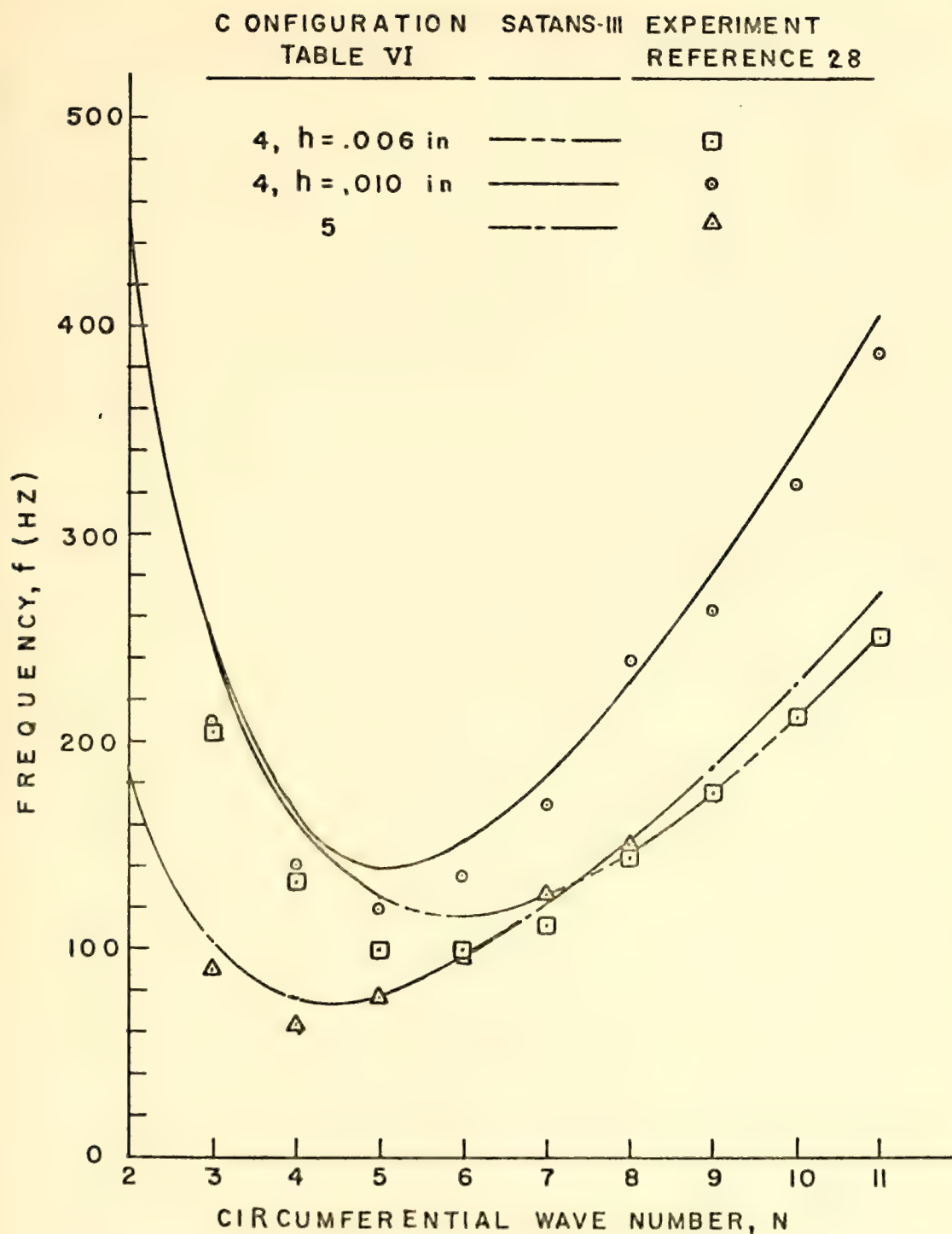


FIGURE 7

MINIMUM NATURAL FREQUENCIES OF 3 CONES

TABLE V

EFFECT OF A LINEARLY VARYING THICKNESS ON MINIMUM FREQUENCIES (Hz)₍₁₎

$$h = .1(x - 1.)(s/S_T) + .1$$

Circum. Wave Number, n	x = 1		x = 2		x = 4		x = 7		x = 10	
	f	m(2)	f	m	f	m	f	m	f	m
1	125.6	1	122.1	1	112.7	1	104.4	1	99.01	1
2	61.26	1	60.72	1	58.44	1	56.09	1	54.28	1
3	33.11	1	32.94	1	32.12	1	31.30	1	30.71	1
4	19.92	1	20.19	1	20.02	1	20.26	1	20.81	1
5	13.62	1	13.85	1	14.80	1	16.43	1	18.92	1
6	10.07	1	10.87	1	13.03	1	17.22	1	21.63	1
7	8.494	1	10.14	1	14.08	1	20.13	1	25.43	1
8	8.285	1	10.91	1	16.37	1	23.25	1	28.87	2
9	9.057	1	12.60	1	18.93	1	26.20	2	32.27	2
10	10.33	1	14.77	1	21.50	2	29.25	2	35.77	2
12	14.24	1	19.65	1	27.05	2	35.75	2	43.11	3
14	19.16	1	25.22	2	33.31	3	42.88	3	51.01	3
16	24.94	1	31.57	2	40.31	3	50.71	4	59.57	4
18	31.56	1	38.73	3	48.10	4	59.28	4	68.84	4
20	38.95	1	46.70	3	56.69	4	68.64	4	78.87	5

(1) Configuration 6, TABLE VI

(2) Axial Half-wave Number

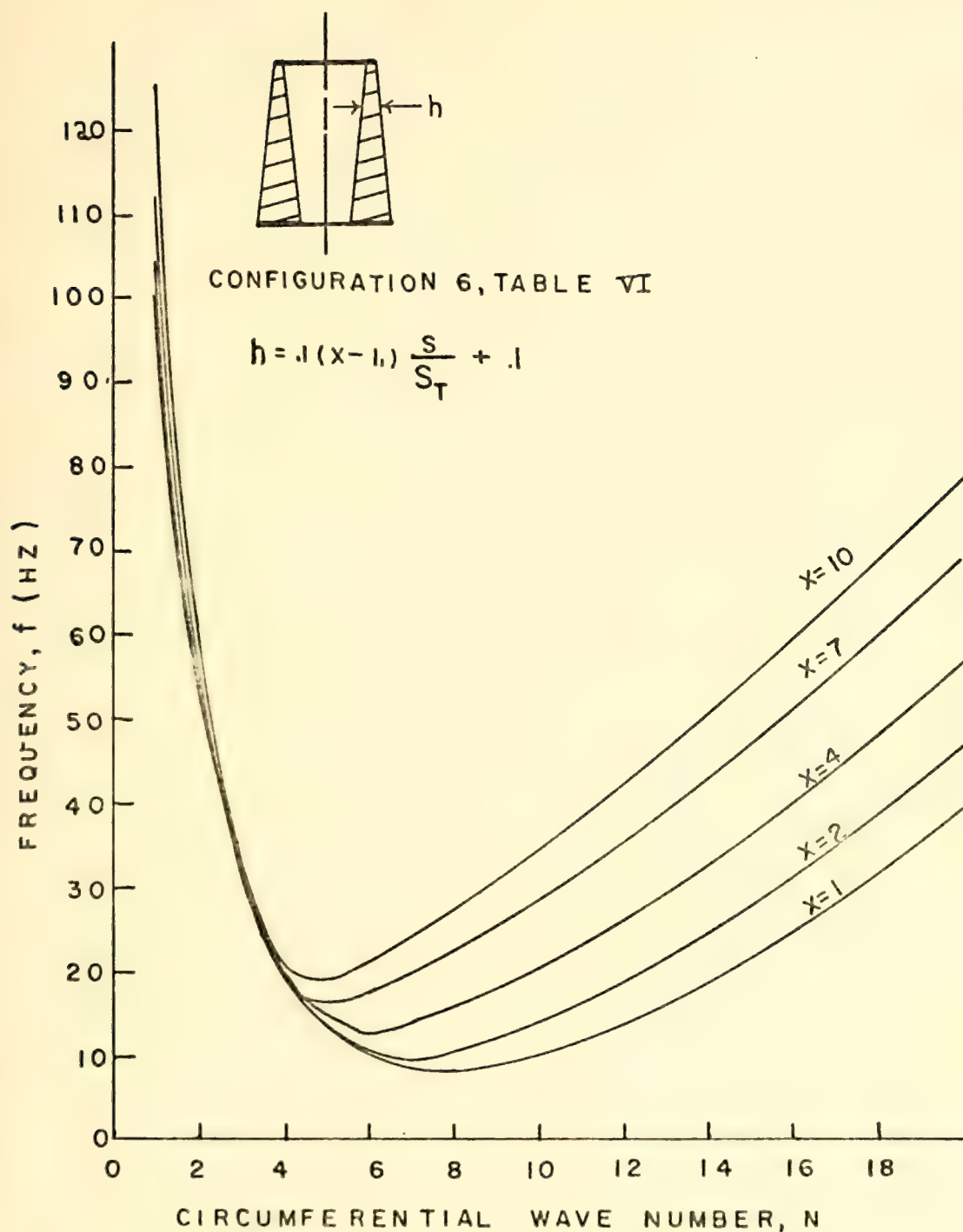


FIGURE 8 EFFECT OF A LINEARLY VARYING THICKNESS ON MINIMUM FREQUENCIES

TABLE VI
SHELL CONFIGURATIONS

Configuration	1	2	3
r (in.)	6.0	100.	$A = .5 - s/3$ $\cos(A) = 1.879$
\bar{r} (in.)	6.0	100.	1.
r_1 (in.)	6.0	100.	.754
r_2 (in.)	6.0	100.	.754
R_s (in.)	∞	∞	3.
R_θ (in.)	6.0	100.	$r/\cos(A)$
h (in.)	.015	.1	.001
h_1 (in.)	.015	.1	.001
h_2 (in.)	.015	.1	.001
ht (in.)	24.0	300.	2.876
S_T (in.)	24.0	300.	3.
$E_y (10^8 \text{ psi})$.3	.3	10^{-8}
ν	.3	.3	.3
$m(10^{-3} \text{ lb-sec}^2/\text{in}^4)$.732	.733	10^3
BNDRY. COND. (1)			
INITIAL EDGE	FS	FS	FS
FINAL EDGE	FS	FS	FS

(1) Table VII

TABLE VI (Continued)

Configuration	4	5	6
r (in.)	$r_1 + .183S$	$r_1 + .274S$	100.0
\bar{r} (in.)			100.0
r_1 (in.)	3.35	4.81	100.0
r_2 (in.)	5.58	10.9	100.0
R_s (in.)	∞	∞	∞
R_θ (in.)	1.017r	1.04r	100.0
h (in.)	$\frac{.006}{.010}$.026	$.1 \cdot (x-1) \cdot (s/S_T) + .1$
h_1 (in.)	$\frac{.006}{.010}$.026	.1
h_2 (in.)	$\frac{.006}{.010}$.026	.1 $\cdot x$
ht (in.)	12.0	21.3	300.
S_T (in.)	12.2	22.15	300.
E_y (10^8 psi)	.28	.148	.3
	.29	.3	.3
v_m (10^{-3} lb-sec ² /in. ⁴)	.740	.4244	.733
BNDRY. COND ₍₁₎			
INITIAL EDGE	C	C	FS
FINAL EDGE	F	F	FS

(1) Table VII

TABLE VII
BOUNDARY CONDITION
SPECIFICATION₍₁₎

Case	Specification
Free (F)	$N_s = \hat{N}_{s\theta} = \hat{Q}_s = M_s = 0$
Freely Supported (FS)	$N_s = M_s = 0$ $V = W = 0$
Simply Supported (SS)	$M_s = 0$ $U = V = W = 0$
CLAMPED (C)	$U = V = W = \phi_s = 0$

(1) The boundary conditions are specified on the total variables N_s , $\hat{N}_{s\theta}$, \hat{Q}_s , ϕ_s , U , V , W and M_s , as depicted in Figure 2, for all Fourier harmonics considered.

APPENDIX C

CONVERTING SATANS-I TO SATANS-III

PART ONE

PROCEDURE FOR ALTERING COMMON BLOCKS IN TRANSFORMING SATANS-I TO SATANS-III.

1. Remove vector X(4,200) from BL4 and insert in BL104
2. " " Z(4,220) " BL6 " " " "
3. " " ZO(4,220) " BL101 " " " "
4. " " Z2(4,220) " " " " "
5. " " Z3(4,220) " " " " "
6. The order of the vectors in common block BL104 is
 Z, ZDOT, X, ZO, Z2, Z3.
7. Change the order of the vectors in common block
 BL24 from DL, DG, DF to DG, DL, DF.
8. The order of the remaining vectors in common blocks
 BL4, BL6 and BL101 should not be altered.

TABLE VIII
CONTENTS OF SATANS-III COMMON BLOCKS

COMMON BLOCK LABEL	CONTENTS
IBL1	MNMAX
IBL2	N(10), MNINIT
IBL3	M0, M1, M2, M3
IBL4	KMAX, KL
IBL5	IBCINL, IBCFNL
IBL6	KLL
IBL7	MNMAXO, MAXD(10), MAXS(10), MAXSY(10), IS(10,10), JS(10,10), ID(10,10), or ⁽¹⁾ JD(10,10), IJS(10) MNMAXO, MAXD(10), MAXS(10), MAXSY (10), MODVIB(3,100), ITEMP(110)
IBL8	LSTEP, ITR
IBL9	MAXM
IBL10	IFREQ, NTHMAX
IBL11	ICORFL, IPASS
IBL12	KMAX1, KMAX2, NCONV
IBL13	ITRMAX, LSMAX
BL1	A(4,4), BEE(4,4), C(4,4)
BL3	PR(10), PX(10), PT(10)
BL4 ⁽²⁾	P(4,4,200), ZF1M(4,4,10), ZF2M(4,4,10), ZF3M(4,4,10), ZF4M(4,4,10)

TABLE VIII (Continued)

BL5	TT(10), MT(10), DT(10), DMT(10)
BL6 ⁽²⁾	SOE, OSE, ALOAD
BL7	D1, S1
BL8	R(200), GAM(200), OMT(200)
BL9	FFS(4,10), ELIS(4), GEES(4,10)
BL10	PHIX(10), PHIT(10), PHI(10)
BL11	OMXI(200), PHEE, T0, T2
BL12	TDLI, TDEL
BL13	OMEG1(4,4), CAPL1(4,4), OMEGL(4,4), CAPLL(4,4), UNIT(4,4)
BL14	LAM2, LSD18, LSD1N
BL15	NU, U1(10), V1(10), W1(10), V2(10), U2(10), W2(10), U3(10), V3(10), W3(10)
BL16	EPS
BL17	DEL
BL18	EL1(4), ELL(4)
BL19	TH(36)
BL20	DEOMX(200)
BL23	JAY(4,4), H(4,4)
BL24 ⁽¹⁾⁽²⁾	DG(4,4,10), DL(4,4,10), DF(4,4,10)
	or DG(4,4,4), RANGE(100,4), TOP, BOTTOM, DELSHF, TOLSHF, RZ(12)
BL25	E(4,4), F(4,4), G(4,4)
BL27	BX3(10), BT3(10), BXT3(10), BE3(10)

TABLE VIII (Continued)

BL28	EXX3(10), ETT3(10), ETX3(10), EXT3(10), EX3(10), ET3(10)
BL29	BX1(10), BT1(10), BXT1(10), BE1(10), BX2(10), BT2(10), BXT2(10), BE2(10)
BL30	EXX1(10), ETT1(10), ETX1(10), EX1(10), ET1(10), EXX2(10), ETT2(10), ETX2(10), EX2(10), ET2(10), EXT2(10)
BL31	DELSQ, EXT1(10)
BL32	TKN, ELAST, CHAR, SIGO
BL34	DEE(4,4,200), DST(4,4,200)
BL100 ⁽³⁾	TEEO, \$DYNMC
BL101 ⁽²⁾	DELSQ
BL102	DELOAD
BL103	MASS(200)
BL104 ⁽¹⁾⁽²⁾	Z(4,220), ZDOT(4,220), X(4,200), ZO(4,220), Z2(4,220), Z3(4,220) or WV(4,203), XV(4,203), YV(4,203), FILL(28), SHFTPT(3,100)
BL110	TX(10), TTH(10), TXT(10), MX(10), MTH(10), MXT(10), QS(10)
BL111	ABZ, ABZO, ABZN, ABZ3, DD2
BLPLOT	IRADII, IGAMMA, IOMEGS, IOMEGT, IDEOMS, IBSTIF, IDSTIF, IBBSTF, IDDSTF, IPR, IPS, IPT, ITT, IMT, IDTT, IDMT, INS, INTH, INSTH, IQS, IMS, IMTH, IMSTH,

TABLE VIII (Continued)

	IU, IV, IW, IPHIS, IPHIT, IPHI, \$PLOTS, \$MODAL
BLPLT1	XRADII(100), YGAMMA(100), YOMEGS(100), YOMEGT(100), YDEOMS(100), YBSTIF(100), YDSTIF(100), YBBSTF(100), YDDSTF(100), YPR(100), YPS(100), YPT(100), YTT(100), YMT(100), YDTT(100), YDMT(100), YNS(100), YNTH(100), YNSTH(100), YQS(100), YMS(100), YMT(100), YMSTH(100), YU(100), YV(100), YW(100), YPHIS(100), YPHIT(100), YPHI(100), XSTATN(100)
BLDATA	TITLE, NO, IMODE, NDIMEN, IPRINT, LCHMAX, IC
BLRUN	IRNAGN
BLK1 ⁽⁴⁾	VMASS, NN2, \$VIBES
BLK2	IVIBES, IVB
BLK3	TWOPI, IBEGIN, IEND, IGO, ISTOP
BLK4	ZERODO, PTFIVE, ONEDO, SMALL, VREAL, VIMAG, AREAL
BLK5	\$FLAG, \$TAG, \$DOVEC
BLK6	NJ, NK, I4, IRGOLD, NUMBER, ITWO
BLK7	SCALEX, SCALEW, SCALE3
BLK8	EPSVIB, EPSVEC, EPSAIT
BLK9	ITR1, ITR2

TABLE VIII (Continued)

BLK10	ASHIFT, ASHFUM, ATSHF, BII, TOLUP, TOLDWN, TOLCLS
BLK11	DIAG(4)
BLK12	NTRY
BLK13	DIF1, DIF2, DIF3, DIF4, TOLLOW, TOLHI, TOLRNG

- (1) Identifies a common block of storage that is overlaid by the vibration analysis portion of the program.
- (2) Identifies a common block that has been altered in transforming SATANS-I to SATANS-III.
- (3) The character \$ indicates a LOGICAL * 1 variable.
- (4) This and subsequent common blocks designated BLKxx are additions required in transforming SATANS-I to SATANS-III.
- (5) Single Precision (REAL*4) variables: JAY, LAM2, LSD18, LSD1N, MASS, MT, NU
- (6) Double Precision (REAL*8) variables: EPSVIB, EPSVEC, EPSAIT, ONEDO, PTFIVE, SCALEW, SCALEX, SCALE3, SMALL, TWOPI, VREAL, VIMAG, WV, XV, YV, ZERO DO

TABLE IX
SOME FORTRAN VARIABLES

AREAL	single precision form of $-(\omega^r T_0)^2 = +1/\alpha^r$
ASHIFT, ASHFUM, ATSHF	spectral shift points, β
BOTTOM	lower bound on frequency range determined in subroutines RANGER and BTM
CHAR	characteristic shell reference length, a
DIAG(4)	diagonal of mass matrix $\bar{\mu}$. Location WV(J, 203), J = 1(1)4 stores the double precision form of DIAG(4).
ELAST	E_0
EPSVIB	eigenvalue convergence criterion
EPSVEC	eigenvector convergence criterion
EPSAIT	Aitkin extrapolation convergence criterion
KEY1	input parameter = MODVIB(1,K) for the Kth vibration analysis
KEY2	input parameter = MODVIB(2,K) for the Kth vibration analysis = N(1)
KEY3	input parameter = MODVIB(3,K) for the Kth vibration analysis; determines \$DOVEC
MODVIB(3,100)	storage array for input parameters KEY1, KEY2, KEY3
RANGE(100, 4)	storage array for frequency range parameters
SCALEW, SCALEX, SCALE3	α^r , α^{r-1} and α^{r-2} respectively
SIGO	σ_0
SHFTPT(3, 100)	storage array for input values; shift points or frequency range boundaries

TABLE IX (Continued)

TEEO	T_o
TKN	h_o
TOP	upper bound of frequency range determined in subroutine RANGER and TOPPER
VMASS	μ_i
VREAL	double precision form of $-(\omega^r T_o)^2$ $= \frac{+1}{\alpha^r} = \frac{+1.}{SCALEW}$
VIMAG	imaginary part of a complex eigenvalue
WV(4, 203), XV(4, 203), YV(4, 203)	double precision solution vectors for the r, r-1 and r-2 vibration analysis iterations
WT(812), XT(812), YT(812)	singly dimensioned counterparts of WV, XV AND YV.
Z(4, 220)	single precision solution vector
ZV(4, 200)	double precision working vector
\$DOVEC	logical operating parameter. If KEY3 = 1, then \$DOVEC is true and the vector convergence test will be performed.
\$FLAG	logical operating parameter. If \$FLAG is true, a real eigenvalue is being dealt with. If \$FLAG is false, the program is dealing with a complex eigenvalue.
\$TAG	logical operating parameter. If \$TAG is true, lower portion of frequency range is being searched. If \$TAG is false, upper portion is being searched.
\$VIBES	Logical input parameter to designate a free vibration problem.

APPENDIX C

PART TWO

MODIFYING SATNAS-I SUBROUTINES

I. Modify common block statements BL4, BL6, BL24, BL101, and BL104, as specified in Part One, in all affected subroutines. In some cases this means replacing one common block statement with two or vice versa. Hereafter all common blocks are referred to as having been modified. The program is written in FORTRAN and all statements referred to are FORTRAN statements.

II. SUBROUTINE SATANS

1. After card 060 insert the statement

```
REAL*8 EPSVIB, EPSVEC, EPSAIT
```

2. After card 100 insert common block

```
IBL7.
```

3. After card 290 insert common blocks BLK1, BLK2, BLK8, BLK9, and BLK11.

4. Replace the dimension statement, card 300, with the two statements

```
DIMENSION MODVIB(3,100), SHFTPT(3,100), TITLE(18)  
EQUIVALENCE (MODVIB(1,1), IS(1,1)), (SHFTPT(1,1),  
Z3(1,146))
```

5. Replace cards 350 and 360 with

```
READ(5,101) NO, $DYNMC, $VIBES, IMODE, NDIMEN,  
NTHMAX, IFREQ, IPRINT,
```

```
1 IBCINL, IBCFNL, KMAX, MNMAX, MAXM, LSMAX, LCHMAX, ITRMAX, IC
```


6. Replace card 490 with the following five cards
IF(.NOT.\$VIBES) GO TO 10
READ(5,108) IVIBES,DIAG,EPSVEC,ITR2
READ(5,109) (((MODVIB(J,I),J=1,3),(SHFTPT(K,I),
K=1,3)), I=1,IVIBES)
10 READ(5,107) IRNAGN
IF(\$VIBES) CALL INITAA
7. After card 650 insert the statement WRITE(6,211)
8. After card 710 insert the statement
IF(\$VIBES) GO TO 11
9. Replace card 750 with the following 7 cards
GO TO 6
card 1180
card 1190
GO TO 6
11 WRITE(6,252) KMAX,ITR1,IVIBES,EPS
WRITE(6,247) CHAR,TKN,ELAST,SIGO,TEEO,NU
6 IF(.NOT.\$PLOTS) GO TO 9
10. Replace cards 1170 and 1200 with the statement
9 IF(NTHMAX.EQ.0) GO TO 7
11. Replace card 1340 with
101 FORMAT(I5,L3,L2,14I5)
12. Insert the following format statements after card
1400.
108 FORMAT(I5,4F1.0,F16.8,I5)
109 FORMAT(3I5,3F15.8)

13. Insert the following format statement after card 2250.

```
252 FORMAT(' ',4X,'NUMBER OF STATIONS-----  
-----',I3,/5X,'M  
LAXIMUM NUMBER OF ITERATIONS-----',  
I3,/5X,'NUMBER OF VIBRATI  
ON ANALYSES-----',I3,/5X,'CONVERGENCE  
CRITERION(EIGENVALUE  
, 3S)-----',E12.4//)
```

III. SUBROUTINE DYNAMC

1. Insert common block BLK1 after card 770.
2. Insert the following statements after card 1870.

```
ICHCK2 = ICHCK2 + ICHCK1  
IF($PLOTS.AND.(ICHCK2.NE.O)) CALL PLOT1(1)  
IF($VIBES) CALL VIBERS(&500)
```

IV. SUBROUTINE PMATRIX

1. After card 200 insert the statement
IMPLICIT LOGICAL*1 (\$)
2. After card 340 insert common blocks BL104, BLK1,
and BLK10.
3. After card 410 insert the statements
ASHFUM = ASHIFT
ATSHF = ASHFUM
4. Place card 830 after card 850.
5. After card 840 insert the statement
IF(\$VIBES) GO TO 2.

6. Replace card 860 with

2 IJ = 1 + KMAX * (MN-1)

V. SUBROUTINE EFG

1. Insert common block BLK1 after card 190

2. After card 220 insert the statements

VMASS = MAS

IF(\$VIBES) MAS = 0.0

VI. SUBROUTINE ABC

1. After card 050 insert the statement

IMPLICIT LOGICAL * 1 (\$)

2. After card 090 insert common blocks BLK1, BLK10, BLK11 and the two statements

DIMENSION TEMP(48)

EQUIVALENCE (TEMP(1),A(1,1))

3. Replace card 190, the RETURN statement, with the following series of statements.

IF (.NOT.\$VIBES) GO TO 4

VMASS = 1.0/(TDEL * VMASS)

DO 2 I = 1, 48

2 TEMP(I) = TEMP(I) * VMASS

DO 3 I = 1,4

BEE(I,I) = BEE(I,I) - ASHFUM*DIAG(I)

3 CONTINUE

4 RETURN

VII. SUBROUTINE OUTPUT

1. After card 500 insert common block BL104
2. After card 640 insert common block BLK1
3. After card 670 insert the statement
 IF(\$VIBES) GO TO 182.
4. After card 890 insert the statement
 IF(\$VIBES) GO TO 991.
5. Replace card 2320 with
 IF(.NOT.\$VIBES) WRITE(6,749)N(MN)

VIII. SUBROUTINE PLOTIT

On cards 080, 090, 100 and 460 change the FORTRAN variable name RANGE to RANGES.

IX. SUBROUTINE DRAWIT

On cards 1860, 1880, 1970, 1980, 1990 and 2000 change the FORTRAN variable name RANGE to RANGES.

APPENDIX C

PART THREE

NEW SUBROUTINES - THEORY AND FLOW CHARTS

Following are descriptions of the subroutines that, added to SATANS-I, constitute the major portion of the conversion from SATANS-I to SATANS-III.

I. SUBROUTINE VIBERS

Subroutine VIBERS is the primary controller for the vibration analysis portion of the program. After the initial input parameters have been printed, subroutine DYNAMC passes control to subroutine VIBERS. Depending on the vibration input parameters subroutine VIBERS calculates and prints the spectral shiftpoint and passes control to the appropriate subroutines. The flowchart for subroutine VIBERS is depicted in Figure 10.

II. SUBROUTINE ITREAL

The purpose of this subroutine is to control the primary iteration process in determining real eigenvalues. The convergence test on the eigenvalues is performed in this subroutine. The vector convergence test is not. That test is performed in subroutine ITRATE. Recall that

$$\alpha^r = \frac{-1}{(\omega^r T_0)^2} = \text{SCALEW}, \quad \text{VREAL} = -(\omega^r T_0)^2$$

and AREAL is the single precision counterpart of VREAL.
The flowchart for subroutine ITREAL is depicted in Figure 11.

III. SUBROUTINE ITRATE

In subroutine ITRATE the primary iteration calculations are performed. In addition, if it is to be performed, the vector convergence test is performed in this subroutine.

As discussed previously the primary iteration scheme uses Potters' Gaussian elimination method. For the forward pass

$$ZV_{i,k} = DEE_{i,j,k} * WV_{j,k+1} - DST_{i,j,k} * ZV_{j,k-1}$$

for $k = 1(1)KMAX2$, $i = 1(1)4$ and $j = 1(1)4$.

Similarly for the backward pass

$$WV_{i,k+1} = ZV_{i,k} - P_{i,j,k} * WV_{j,k+2}$$

for $k = 1(1)KMAX2$, $i = 1(1)4$ and $j = 1(1)4$

Separate calculations are used to start and finish the calculations as well as handle shells with initial and/or final poles.

WV is the solution vector for the r^{th} iteration. XV and YV are, respectively, the solutions for the $r-1$ and $r-2$ iterations.

WT, XT, and YT are the singly dimensioned versions of, respectively, WV, XV and YV. The flowchart for subroutine ITRATE is depicted in Figure 12.

IV. SUBROUTINE ITCPLX

A. CONVERGENCE FAILURE

A few of the conditions that may cause the inverse iteration scheme to fail are:

1. Eigenvalues may be too close together for separation to occur in the specified maximum number of iterations.
2. A complex conjugate pair of eigenvalues may cause convergence failure.
3. If the two lowest eigenvalues are of equal magnitude and opposite sign, convergence is extremely difficult, if not impossible. This may be caused by shifting. If, for example, the shift point is 6 and three eigenvalues are 4, 6 and 8, the resulting lowest two are plus and minus 2.
4. The occurrence of a repeated eigenvalue almost prohibits passing the vector convergence test as do conditions two and three.
5. A poorly conditioned matrix or shifting too close to an eigenvalue may cause a numerically unstable situation in the machine.

The above conditions have not yet occurred when using SATANS-III, but were forced to occur during prototype testing.

B. DESCRIPTION OF SUBROUTINE ITCPLX

If the primary inverse iteration scheme fails to converge, control is passed to subroutine ITCPLX. The method of least squares is used to determine the two eigenvalues closest to the shift point, whether real or a conjugate pair. The eigenvector is not calculated. In the case of the conjugate pair the vector is of no interest (in this application) and in the case of two real eigenvalues a further refinement takes place which automatically includes determination of the two vectors.

C. LEAST SQUARES PROCEDURE

The method of least squares is a procedure for minimizing a function [Refs. 7, 9, 10]. Assume the solution to a problem is found by determining x and y in the following system.

$$\begin{aligned} f(x,y) &= a_1x + a_2y - a_3 = 0 \\ g(x,y) &= b_1x + b_2y - b_3 = 0 \end{aligned} \tag{C-1}$$

First form the function $h(x,y) = f^2(x,y) + g^2(x,y)$. Subsequently form the partial derivatives $\left. \frac{\partial h}{\partial x} \right)_y$ and $\left. \frac{\partial h}{\partial y} \right)_x$. In the r^{th} step solve for x^r at the minimum with respect to x with the expression resulting from the first

partial derivative. Substitute this x^r in the expression resulting from the second partial derivative and solve for y^r at the minimum with respect to y . Substitute this y^r in the first expression and solve for x^{r+1} . Alternately solve for successive x^r and y^r until they meet some convergence criteria.

D. LEAST SQUARES IN MATRIX NOTATION

, System (C-1) may be written as

$$\begin{bmatrix} a_1 & a_2 \\ b_1 & b_2 \end{bmatrix} \begin{Bmatrix} x \\ y \end{Bmatrix} - \begin{Bmatrix} a_3 \\ b_3 \end{Bmatrix} = 0$$

and in general as

$$\begin{aligned} [a_{ij}] \{u_j\} - \{v_i\} &= 0 & i &= 1(1)m \\ & & j &= 1(1)n \end{aligned} \quad (C-2)$$

or as

$$A U - V = 0 \quad \text{where } m \text{ need not equal } n.$$

The least squares procedure may then be performed by forming

$$A^T A U - A^T V = 0 \quad \text{and solving for the } u_j.$$

By way of demonstration start with (C-2) and perform the matrix multiplication and rewrite as

$$\left\{ \sum_{j=1}^n a_{ij} u_j - v_i \right\} = 0 \quad i = 1(1)m$$

Form the function

$$h = \sum_{i=1}^m \left(\sum_{j=1}^n a_{ij} u_j - v_i \right)^2$$

and the partial derivatives

$$\left. \frac{\partial h}{\partial u_k} \right)_{\substack{u_j \\ j \neq k}} = 2 \sum_{i=1}^m a_{ik} \left(\sum_{j=1}^n a_{ij} u_j - v_i \right) = 0$$

for $k = 1(1)n$.

Delete the 2 as immaterial to the minimizing procedure

and write the $\left. \frac{\partial h}{\partial u_k} \right)_{\substack{u_j \\ j \neq k}}$ as a system. Note that the row vector

$$[a_{ik}] = \{a_{ij}\}^T \quad \text{for } j = k.$$

$$\sum_{i=1}^m a_{ik} \left(\sum_{j=1}^n a_{ij} u_j - v_i \right)$$

$$= [a_{ik}] \left(\sum_{j=1}^n a_{ij} u_j - v_i \right) = 0$$

$$[a_{ik}] ([a_{ij}] \{u_j\} - \{v_i\}) = 0$$

$$[a_{ij}]^T [a_{ij}] \{u_j\} - [a_{ij}]^T \{v_i\} = 0$$

$$A^T A U - A^T V = 0$$

E. SUBROUTINE PROCEDURE

Assume that the two eigenvalues closest to the shift point are the roots of the quadratic equation $x^2 - ax - b = 0$. ITCPLX determines a and b from which the roots may be extracted.

The equation is true for any vector $Z = \{z\}$.

$$(x^2 - ax - b) Z = x^2 Z - ax Z - b Z = 0$$

From the iteration process on the r^{th} iteration

$$xZ = \alpha^{r+1} Z^{r+1} \quad \text{where } \alpha^{r+1} \text{ is the maximum}$$

element in Z^{r+1} before scaling. It then follows that

$$\alpha^{r+2} \alpha^{r+1} Z^{r+2} - a \alpha^{r+1} Z^{r+1} - b Z^r = 0$$

Rewriting the above

$$a \alpha^{r+1} Z^{r+1} + b Z^r = \alpha^{r+2} \alpha^{r+1} Z^{r+2}$$

and

$$[Z] \begin{Bmatrix} \alpha^{r+1} & a \\ & b \end{Bmatrix} = \alpha^{r+2} \alpha^{r+1} Z^{r+2}$$

where

$$[Z] = [Z^{r+1} \ Z^r]$$

Performing the least squares procedure

$$[Z]^T [Z] \begin{Bmatrix} \alpha^{r+1} & a \\ & b \end{Bmatrix} = \alpha^{r+2} \alpha^{r+1} [Z]^T \{Z\}^{r+2}$$

Moving the α^{r+1} to the first column and rewriting

$$\begin{bmatrix} \alpha^{r+1} & Z^{r+1T} & Z^{r+1} & Z^{r+1T} & Z^r \\ \alpha^{r+1} & Z^rT & Z^{r+1} & Z^rT & Z^r \end{bmatrix} \begin{Bmatrix} a \\ b \end{Bmatrix} \\ = \alpha^{r+1} \alpha^{r+2} \begin{Bmatrix} Z^{r+1T} & Z^{r+2} \\ Z^rT & Z^{r+2} \end{Bmatrix}$$

The α^{r+1} and Z^{r+1} are solved for by Potters' Gaussian elimination procedure. The two eigenvalues are then $s + t$ and $s - t$ where $s = \frac{a}{2}$ and $t = \frac{\sqrt{a^2 + 4b}}{2}$. The test for two real roots versus a complex conjugate pair is the sign of the discriminant $a^2 + 4b$. The two convergence tests are

$$\left| \frac{|s^{r+1}| - |s^r|}{s^{r+1}} \right| \quad \text{less than EPSVIB}$$

and

$$\left| \frac{|t^{r+1}| - |t^r|}{t^{r+1}} \right| \quad \text{less than EPSVIB.}$$

F. SUBROUTINE FORTRAN VARIABLES

In subroutine IPCPLX the Fortran Variables are

$$\begin{array}{ll}
 \text{SCALEW} &= \alpha^{r+2} & \text{WT(I)} &= z^{r+2} \\
 \text{SCALEX} &= \alpha^{r+1} & \text{XT(I)} &= z^{r+1} \\
 \text{SCALE3} &= \alpha^r & \text{YT(I)} &= z^r \\
 \text{ZA} &= a & \text{ZB} &= b \\
 \text{VREAL} &= s^{r+1} & \text{VIMAG} &= t^{r+1} \\
 \text{OLDVR} &= s^r & \text{OLDVI} &= t^r
 \end{array}$$

The system set-up is

$$\begin{bmatrix} \text{B} \\ \text{E} \end{bmatrix} \begin{bmatrix} \text{C} \\ \text{F} \end{bmatrix} \begin{Bmatrix} \text{ZA} \\ \text{ZB} \end{Bmatrix} = \begin{Bmatrix} \text{D} \\ \text{G} \end{Bmatrix}$$

where

$$\text{B} = \text{SCALEX} * \left(\sum_{\text{I}=\text{IGO}}^{\text{ISTOP}} \text{XT(I)} * \text{XT(I)} \right)$$

and

$$\text{G} = \text{SCALEX} * \text{SCALEW} * \left(\sum_{\text{I}=\text{IGO}}^{\text{ISTOP}} \text{YT(I)} * \text{WT(I)} \right)$$

etc.....

and

$$\text{VREAL} = 0.5 * \text{ZA}$$

$$\text{VIMAG} = 0.5 * \text{DSQRT} (\text{ZA} * \text{ZA} + 4.0 * \text{ZB})$$

G. PERFORMANCE OF SUBROUTINE ITCPLX

As mentioned before, ITCPLX was never invoked by SATANS-III during the execution of the test cases. However, during prototype testing it was possible to evaluate the procedure extensively [Refs. 7, 8, 16 and 17]. In all cases, whenever the inverse iteration scheme failed subroutine ITCPLX returned the correct eigenvalues, both real and complex. This subroutine provides an excellent backup and diagnostic tool for the basic solution procedure.

Since the subroutine uses Potters' scheme to determine the z^{r+1} it is subject to the same general ill-conditioning problem that the primary scheme is subject to in this respect. A second problem arises when t^r is extremely small. This is a highly unlikely case in practice in regards to this application. In the case of total non-convergence by both schemes the results of the last two iterations of both schemes are printed along with the information on whether they would be real or complex values. This information is valuable in analyzing a difficult problem. The flowchart for subroutine ITCPLX is depicted in Figure 13.

V. SUBROUTINE RANGER

A. FREQUENCY RANGE SEARCH

The primary objective in a frequency range search operation is to provide some method of ensuring that all the frequencies in the given range are determined or, if missed, determining which are missed. This is accomplished

in two ways in SATANS-III. Each eigenvalue is determined three times in covering a range. For each eigenvalue determined, the mode shape is simultaneously determined and printed once, along with the eigenvalue (frequency). Determining an eigenvalue three times is time consuming but reduces the chance of missing a mode and examining the mode shapes determined is an easy way of spotting a missed mode.

The method employed uses the basic iteration scheme to actually determine the eigenvalues. No a priori knowledge of the number or distribution of frequencies in the range is assumed. The amount of work involved is directly proportional to the number, separation and distribution of frequencies in the range and the operating parameters.

The calculations involve two primary subroutines, RANGER and ADJUST. Subroutine RANGER contains the primary search scheme and initial eigenvalue determination scheme. Two other subroutines are involved, BTM and TOPPER, which determine the lowest and highest frequencies in the range, respectively.

The only additional inputs by the user for this operation are the frequency range endpoints in Hz.

B. SEARCH SCHEME

The eigenvalues naturally determined by the system of four second order equations are negative ($-\omega^2 T_o^2$). It is easier to search the field of negative numbers rather than alter the set-up of the problem to yield positive numbers. For this reason the lower bound of the range,

BOTTOM, is the negative number smallest in magnitude and corresponds to the lowest frequency. Similarly the upper bound of the range, TOP, is the negative number largest in magnitude and corresponds to the highest frequency.

For example if the range from 1.59 Hz to 5.29 Hz is to be searched then $BOTTOM = -(6.28(1.59)1.0)^2 = -100$ where $6.28 = 2 \text{ PI}$ and $1.0 = T_0$ and $TOP = -(6.28(5.29)1.0)^2 = -1,100$. These two numbers establish the initial range. This initial range is subsequently partitioned into a number of smaller ranges as new eigenvalues are determined, and each smaller range is eliminated when all eigenvalues within that range have been determined.

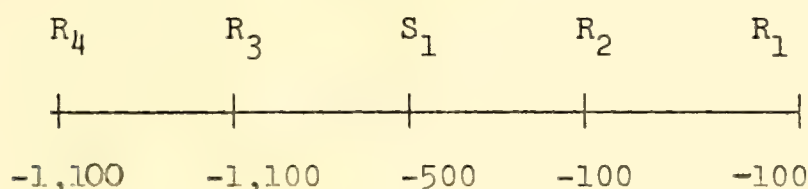
Each range has associated with it four parameters stored in the array RANGE (100,4). For the sake of clarity the elements of this array will be referred to as R_1 in the example that follows. For a given range, K, the elements of the array RANGE are

EXAMPLE

1. Lowest eigenvalue in the range, $R_1 = -100$.
RANGE(K,1)
2. Either the lowest eigenvalue or $R_2 = -100$.
the maximum value in the band-
width from which it was
determined. RANGE(K,2)

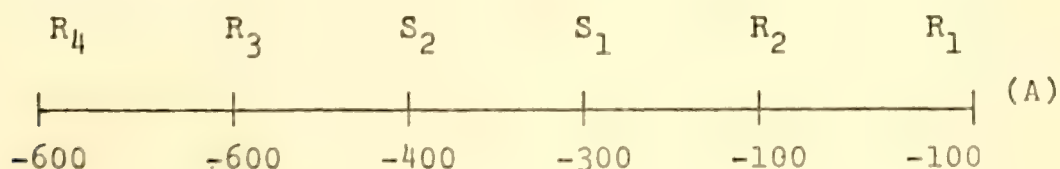
3. Either the highest eigenvalue $R_3 = -1,100.$
or the minimum value in the
bandwidth from which it was
determined. $RANGE(K,3)$
4. Highest eigenvalue in the $R_4 = -1,100.$
range. $RANGE(K,4)$

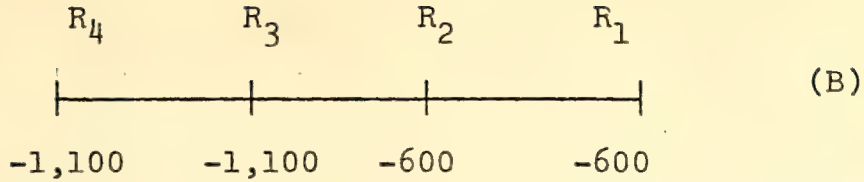
Therefore, $RANGE(K,J)$ for $J = 1(1)4$ is $(-100., -100., -1,100., -1,100.)$, and is represented graphically as



The range of frequencies is searched by choosing a suitable spectral shift point. (Present program parameters call for 40% up from the bottom of the range specified by R_2 . This may be a user specified parameter by altering the statement $TOLCLS = .4$ in subroutine INITAA). In the example the first shift point is -500 , S_1 .

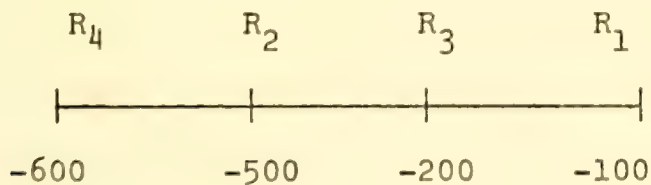
Assume a new eigenvalue, -600 , is determined. The initial range is then partitioned in two ranges as shown below.





The above partitioning occurs each time a new eigenvalue is determined. The next shift point, S_1 , is -300.

Assume that there are no more eigenvalues in the range from -100 to -600. It is the nature of the inverse iteration process that the eigenvalue closest to the spectral shift point will be determined. This is -100 in the example. Because of this property it is assumed that no other eigenvalue exists within ± 200 of S_1 . (Otherwise it should have been determined.) If the eigenvalue -100 is determined from the shift point -300 then R_2 is set to the maximum value of the bandwidth. $R_2 = -300 + (-300 - (-100)) = -500$. The next shift point is $S_2 = -400$ (40% down from the top.). From the spectral shift point the higher eigenvalue, -600, will be determined and a similar calculation for R_3 is performed; $R_3 = -400 - (-600 - (-400)) = -200$. The following situation then exists

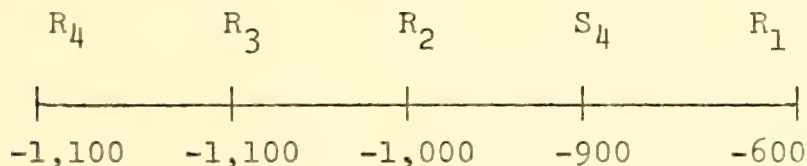


This is how a range is eliminated as being completely covered. The range elimination test is

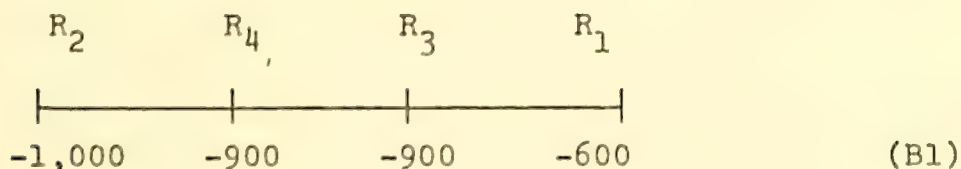
$$\text{Is } R_2 = < \text{TOLRNG} * R_3 ? \quad (\text{TOLRNG} = 1.0 - (.4 * \text{EPS}))$$

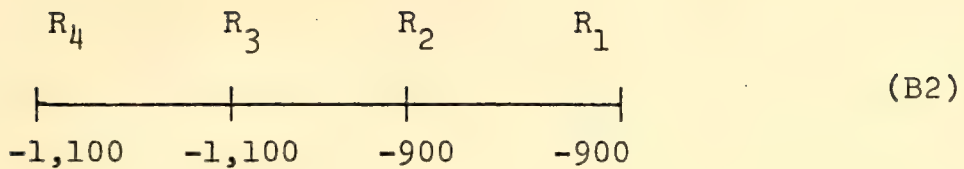
and is intended to prevent missing a mode near the center of the range when a shift point of 25% from the top or bottom is used. (TOLRNG is set in subroutine INITAA.)

The first shift point, S_3 , in the second range, (B), is -800, and assume further that the lower eigenvalue of -600 has been determined (for the third time !!!). The situation is as follows



The next shift point (40% down from the top as specified by R_3) is $-900 = S_4$. From this spectral shift point assume that an eigenvalue of -900 is determined. The partition would then be





with range (B1) being immediately eliminated. The process would be repeated with range (B2).

A range, or portions thereof, may be eliminated because no real eigenvalue is found within the range, or because an eigenvalue outside the range is found. Consideration must also be given to the situation where ill-conditioning would cause the primary scheme to fail and two real eigenvalues might be determined by subroutine ITCPLX.

In deciding if an eigenvalue has been previously determined when eliminating a range, consideration should be given to the desired results of the problem. For example, is it necessary to know all frequencies in a range even if four of them differ by less than 1%? A set of parameters (TOLLOW and TOLHI) determine the degree of separation that defines individual eigenvalues and are presently set at $\pm 1/2\%$. They are set in subroutine INITAA. Thus, if two eigenvalues differ by less than $\pm 1/2\%$ they are defined as one eigenvalue.

Subroutine RANGER has incorporated an Aitkin extrapolation to accelerate the convergence rate of the eigenvalues. To further reduce computation time the convergence criteria, EPSAIT, on the accelerated

eigenvalues is different from the criteria, EPSVIB, for the refined eigenvalues. EPSAIT should be commensurate with the chosen separation criteria. EPSAIT is currently set at .01 in subroutine INITAA.

Since the lowest frequencies are of most interest the search scheme is biased toward the lower frequencies. The shift points chosen first are in the lower portion of the range. Second is the choice of vectors. For the first vector the initial guess is all ones. Subsequently the guess is the difference between the r^{th} and $r-2$ iterated vector. The iterated vectors are richer in the lower modes than the higher modes. (Consider the expansion of an arbitrary vector in the set of orthogonal eigenvectors.) This amounts to a pseudo sweeping technique. The actual calculation of the difference of the two vectors is performed in subroutine ITRATE. Figure 9 depicts the search scheme schematic. The flowchart for subroutine RANGER is depicted in Figure 14.

VI. SUBROUTINE ADJUST

Subroutine ADJUST is the second of the subroutines involved in the frequency range search operation. (The first was subroutine RANGER.) Three main functions are performed by this subroutine.

A. Newly determined eigenvalues and eigenvectors are refined.

B. Range partition and elimination calculations are

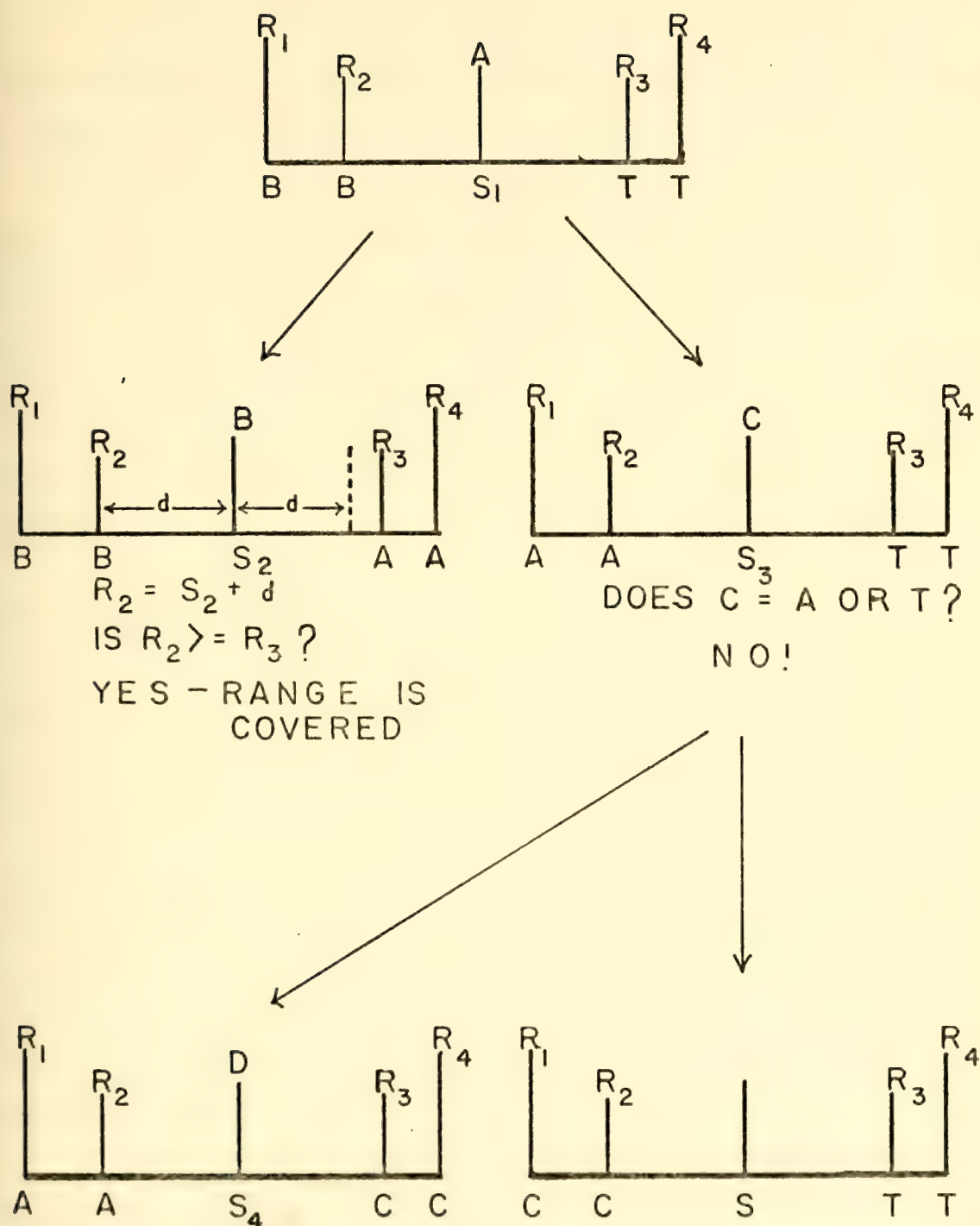


FIGURE 9 SEARCH SCHEME SCHEMATIC

performed including the range elimination test.

C. The situation of a complex conjugate pair or two real eigenvalues, both in the range, only one in the range or both outside the range, is handled in this subroutine.

In refining a newly determined eigenvalue, a new shift point close to the subject eigenvalue is chosen. How close is determined by the parameter TOLSHF (currently set at 90%) set in subroutine INITAA. A new vector is not obtained and the iteration begins with the last obtained vector. Figure 15 depicts the flowchart for subroutine ADJUST.

VII. SUBROUTINE BTM

Subroutine BTM is one of two minor subroutines (BTM and TOPPER) called in subroutine RANGER. The function of BTM is to determine the minimum eigenvalue of the range. The initial shift point used is the lower bound specified by the user in his input statement.

If a real eigenvalue cannot be found at the first shift point a new shift point 10% up the range is tried. This continues until the range is completely covered or a real eigenvalue is determined.

A form of the Aitkin extrapolation is used to accelerate the initial convergence rate.

The vector convergence test is always performed in this subroutine in determining the minimum eigenvalue. The flowchart for subroutine BTM is depicted in Figure 16.

VIII. SUBROUTINE TOPPER

Subroutine TOPPER operates in a manner analogous to subroutine BTM in determining the maximum eigenvalue of the range.

The main differences are the initial shift point, which is the upper bound specified by the user, and the fact that the vector convergence test is not performed unless specified by the user. The flowchart for subroutine TOPPER is depicted in Figure 17.

IX. SUBROUTINE INITAA

Subroutine INITAA, called only in a vibration analysis, sets the operating parameters of the program.

IBEGIN, IEND, IGO and ISTOP are do-loop begin and terminate parameters to ease handling of the eigenvectors as doubly and singly dimensional arrays.

The rest of the program is self-explanatory. See the program listing. Figure 18 depicts the flowchart for subroutine INITAA.

X. SUBROUTINE START

Subroutine START initializes iteration parameters and the starting vector. The flowchart for subroutine START is depicted in Figure 19.

XI. SUBROUTINE VECOUT

This subroutine controls the printed output for the vibration analyses. Several operations are performed in

addition to printing output.

A. The eigenvalues are converted to real time cycles per second (Hz).

B. A check is made for imaginary frequencies.

C. The double precision solution vector $WV(I)$ is mapped into single precision space prior to calling subroutine OUTPUT which prints the solution vector.

Examples of all possible printed messages are presented in Figure 20. Lines in braces are optional or alternate possibilities.

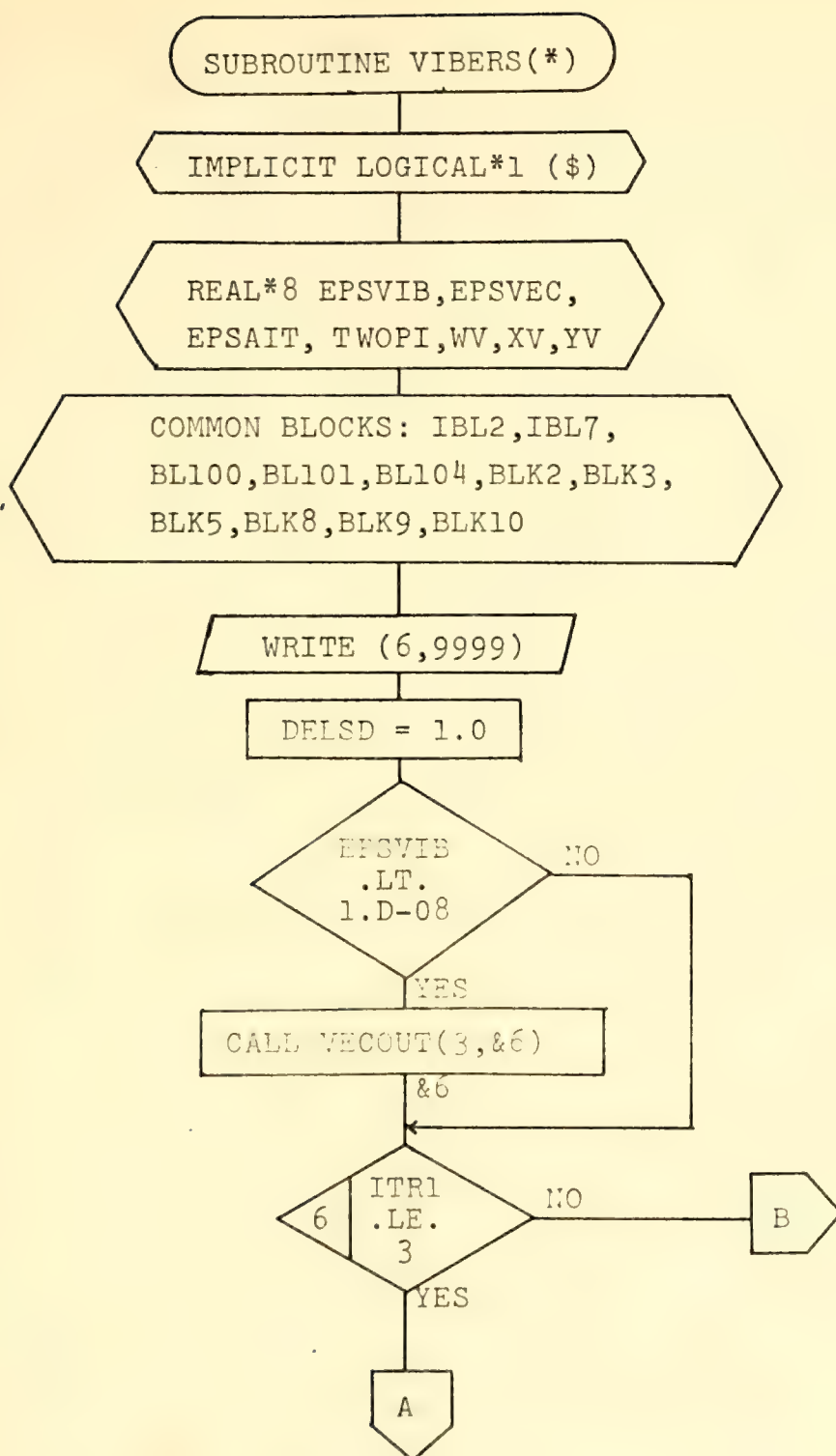


FIGURE 10. SUBROUTINE VIBERS(*) FLOWCHART

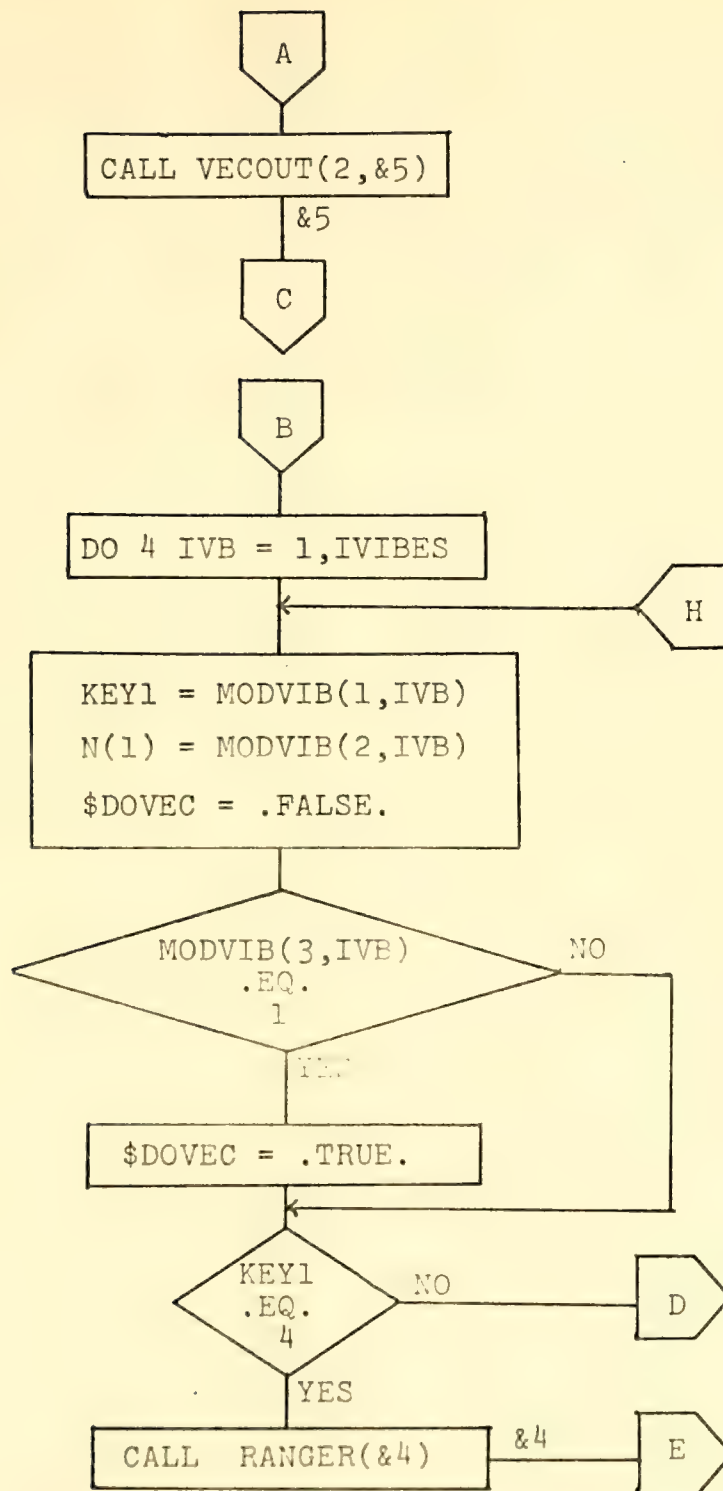


FIGURE 10 continued

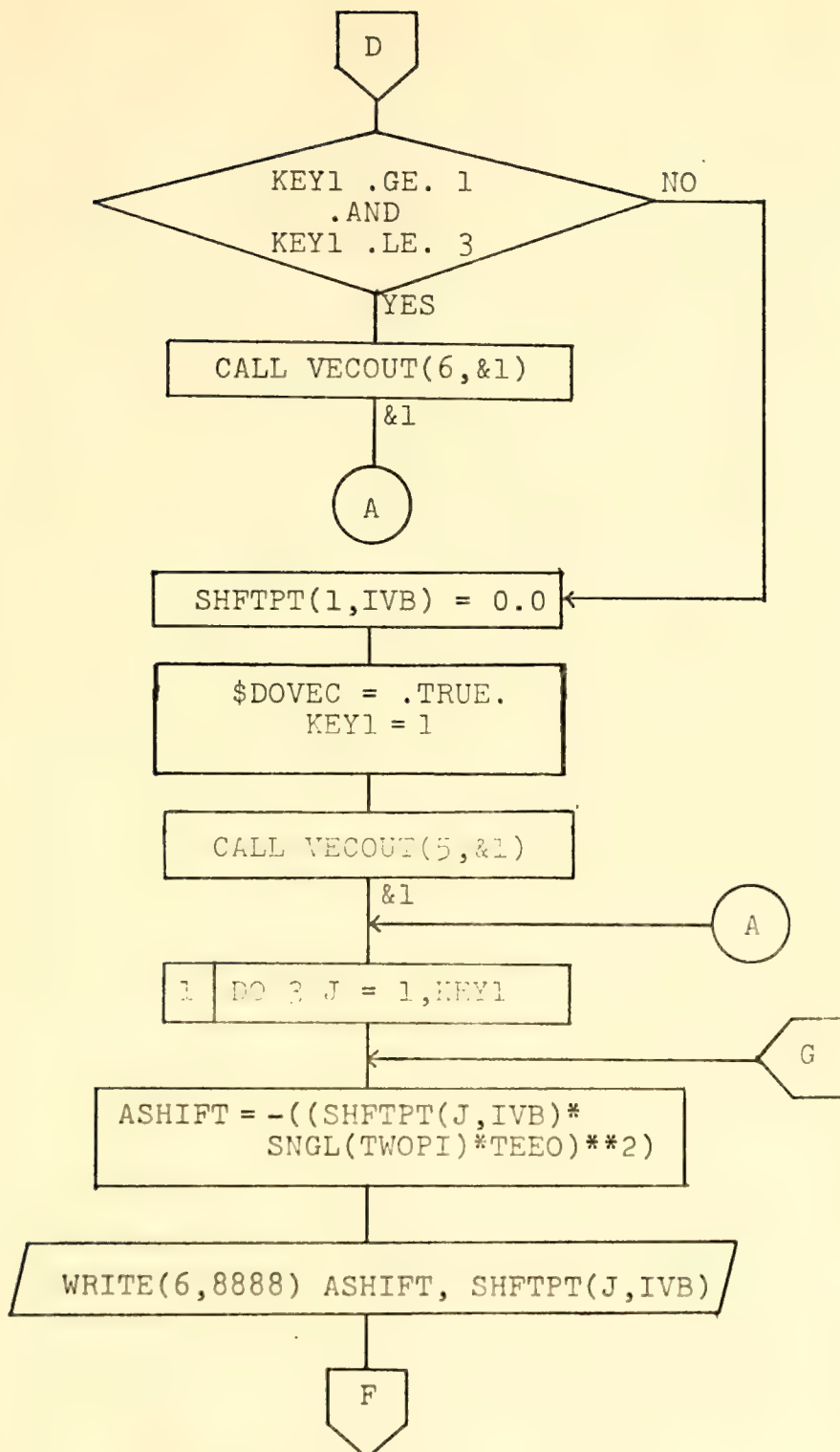


FIGURE 10 continued

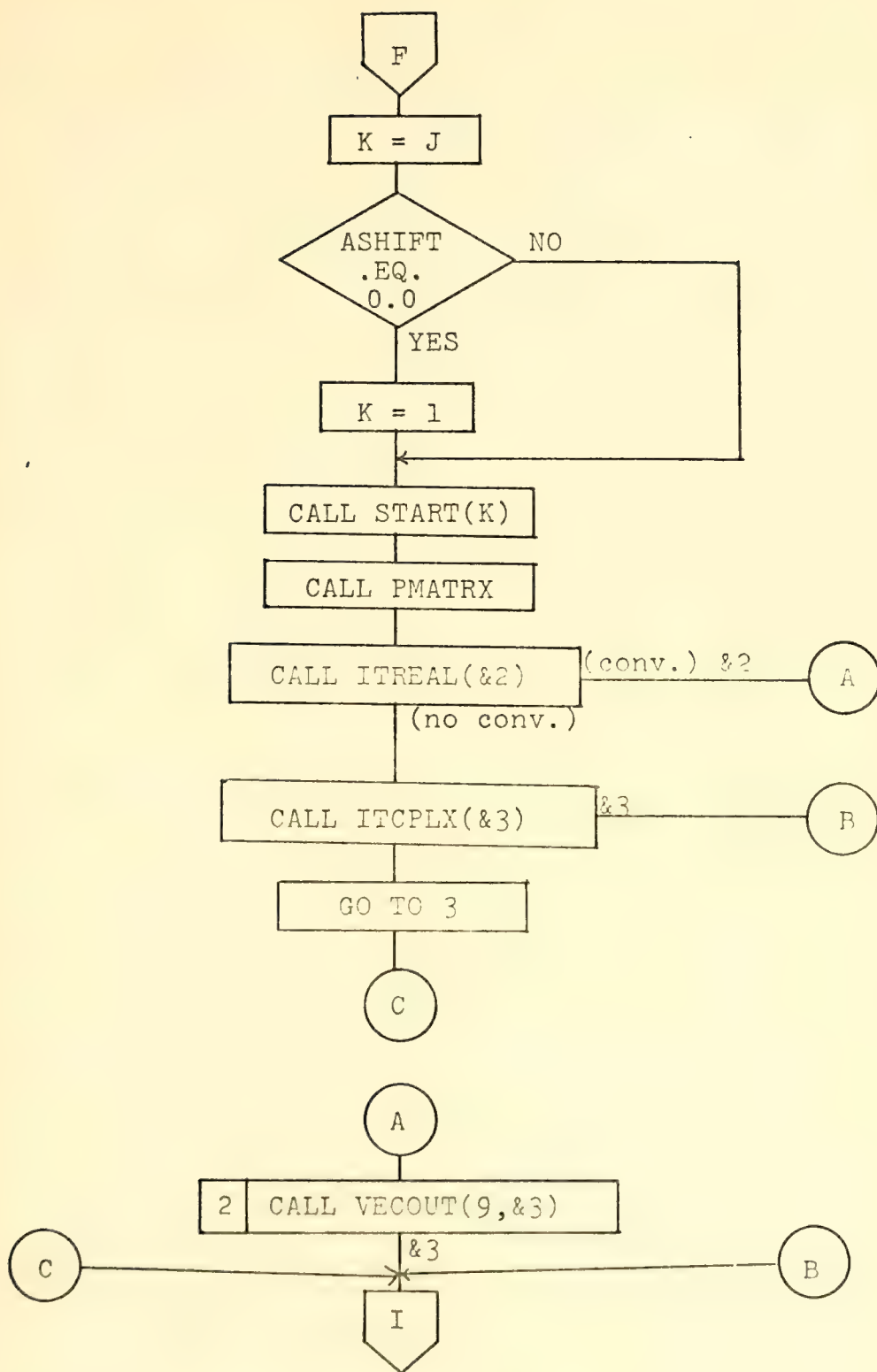


FIGURE 10 continued

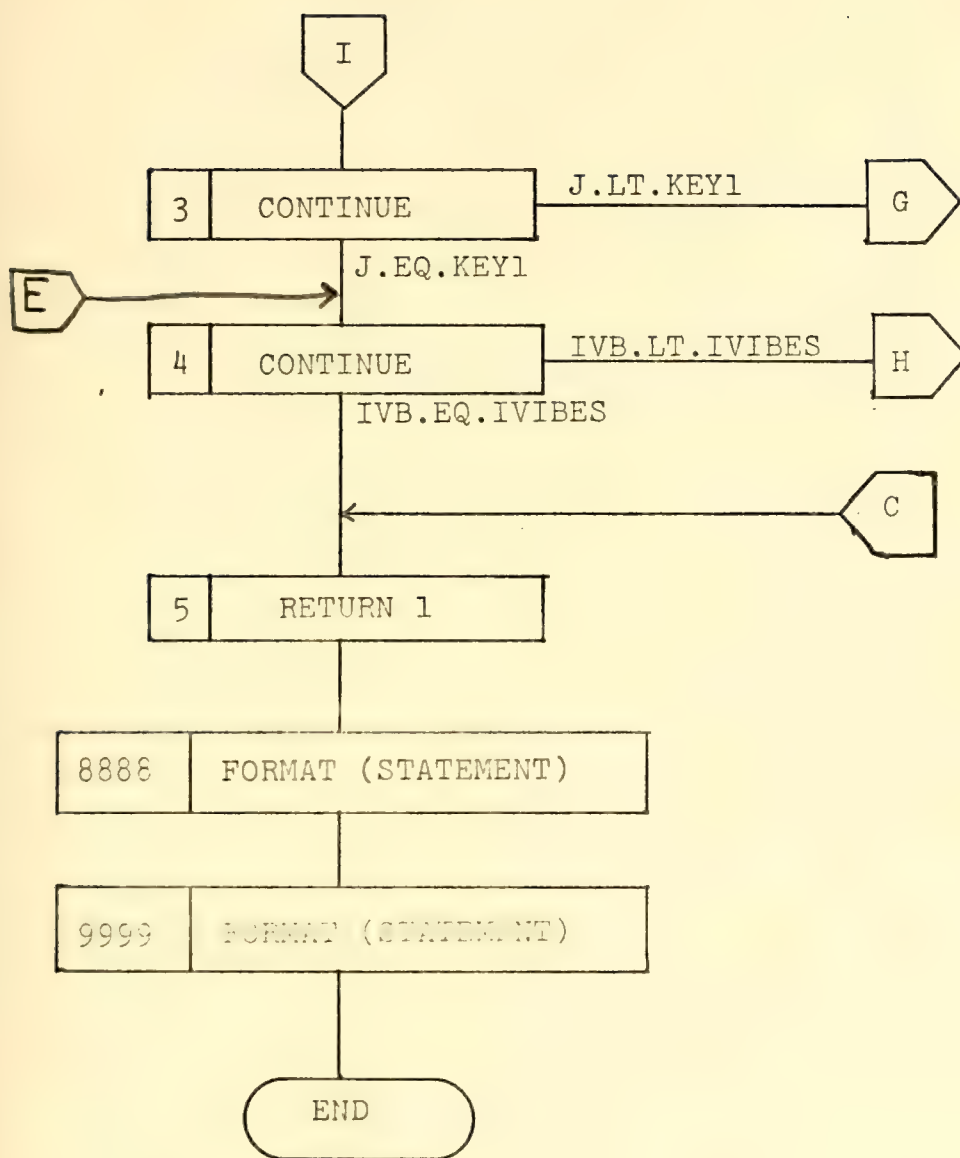


FIGURE 10 continued

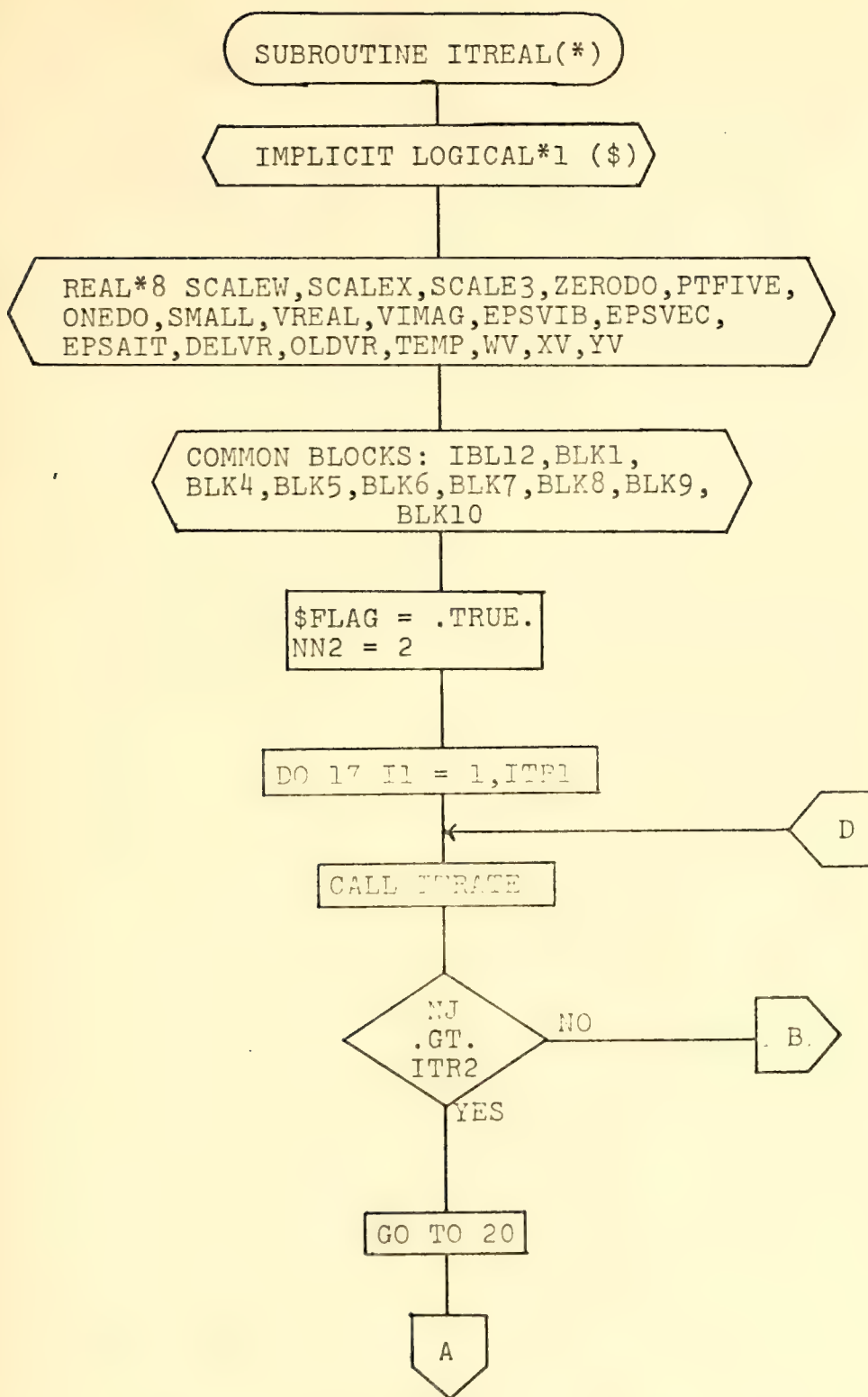


FIGURE 11. SUBROUTINE ITREAL(*) FLOWCHART

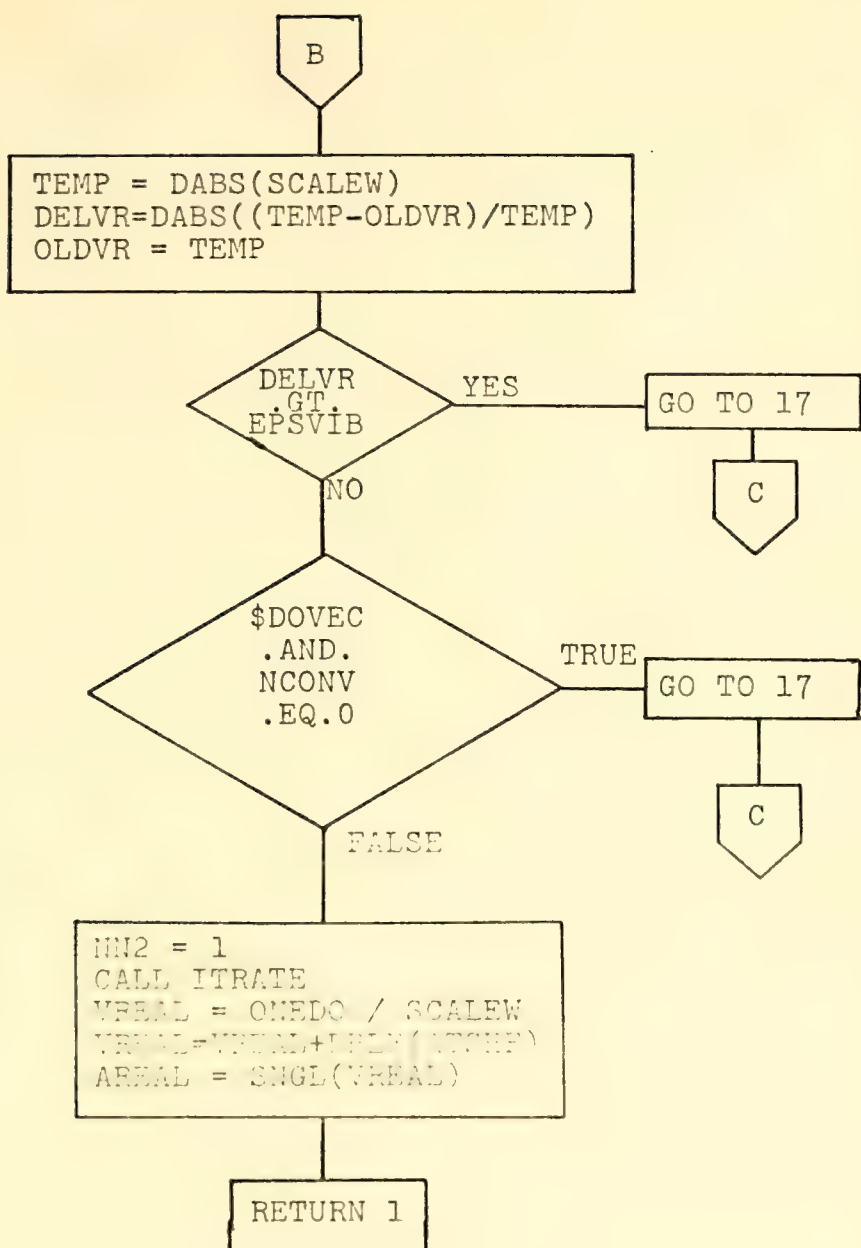


FIGURE 11 continued

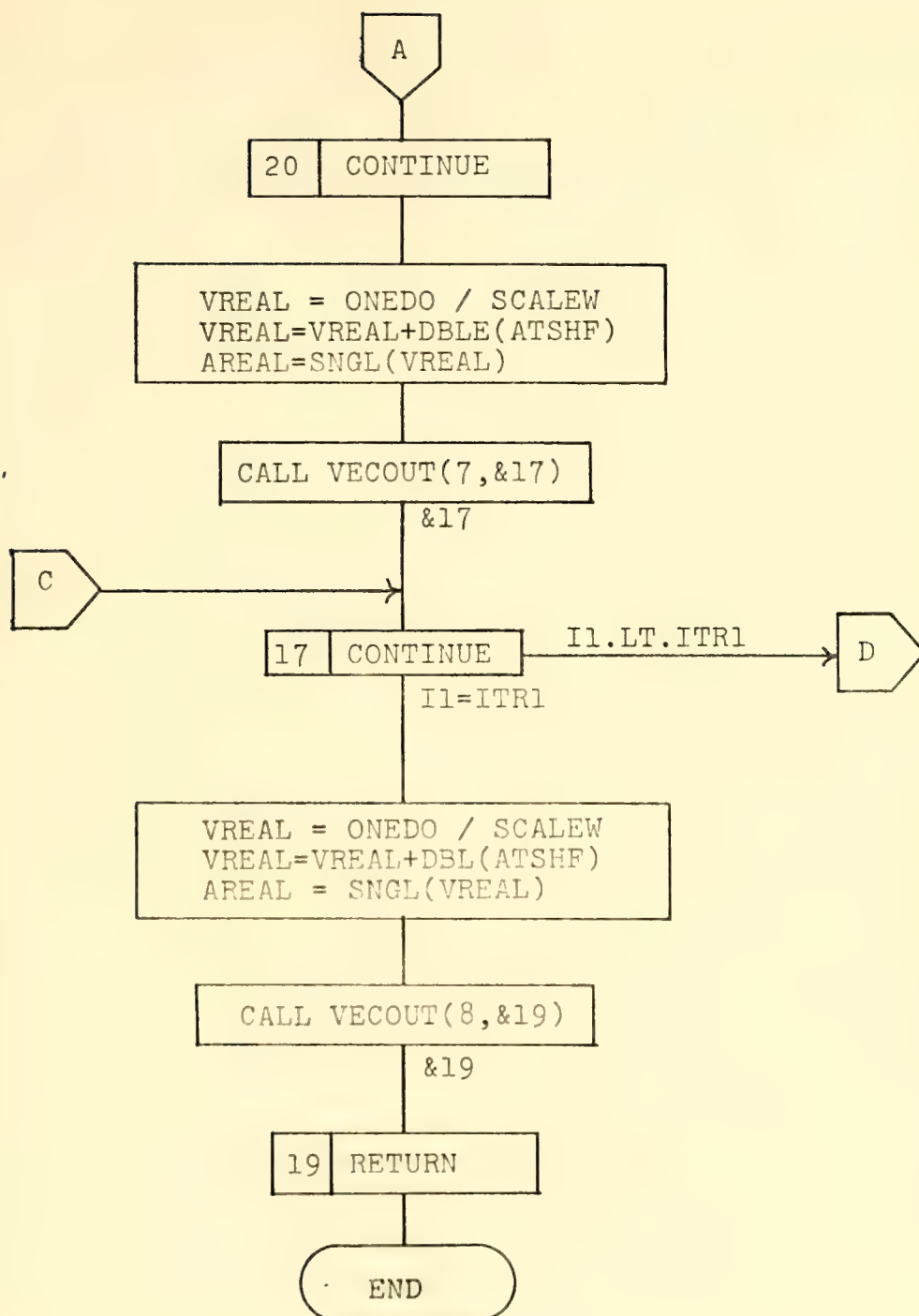


FIGURE 11 continued

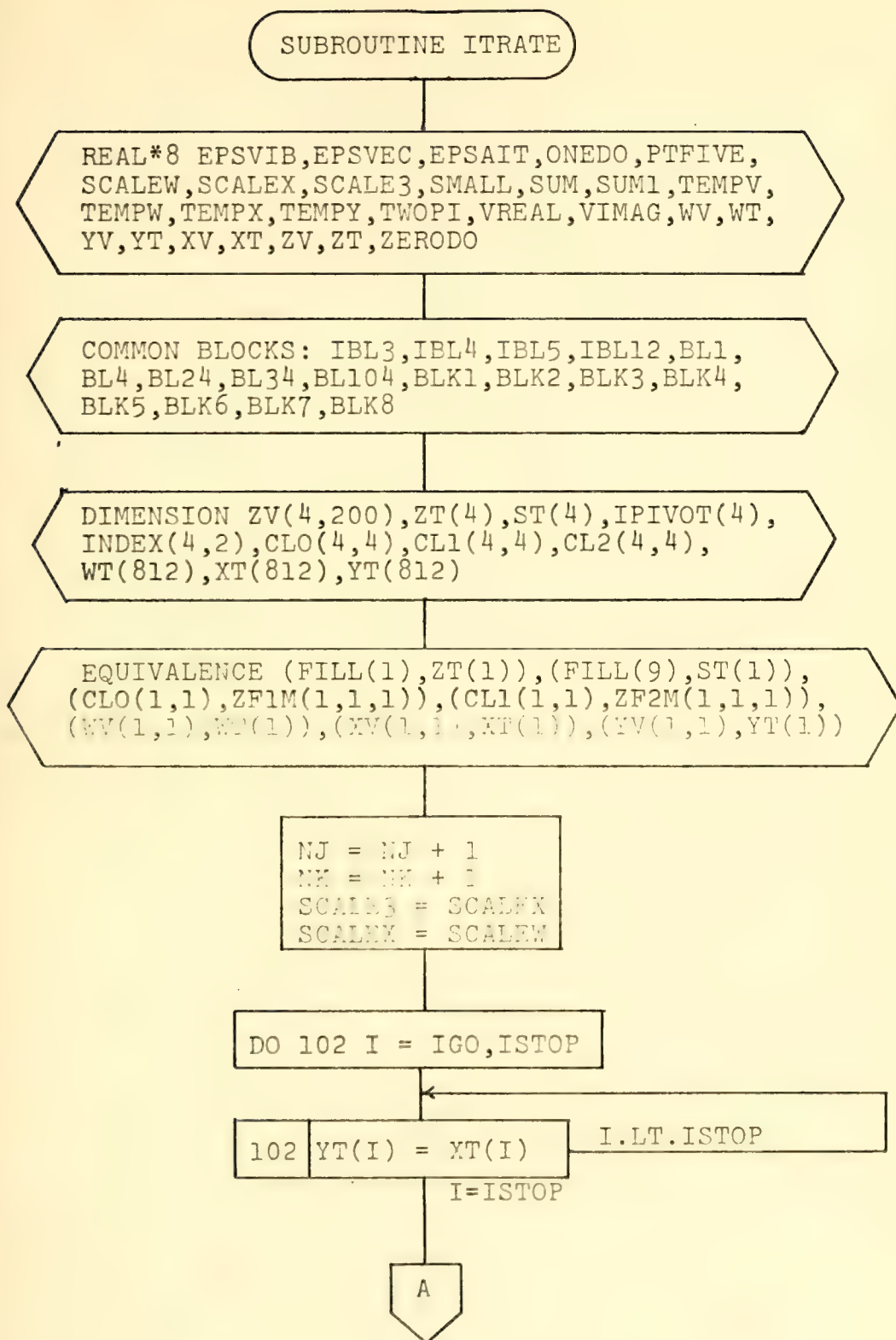


FIGURE 12. SUBROUTINE ITRATE FLOWCHART

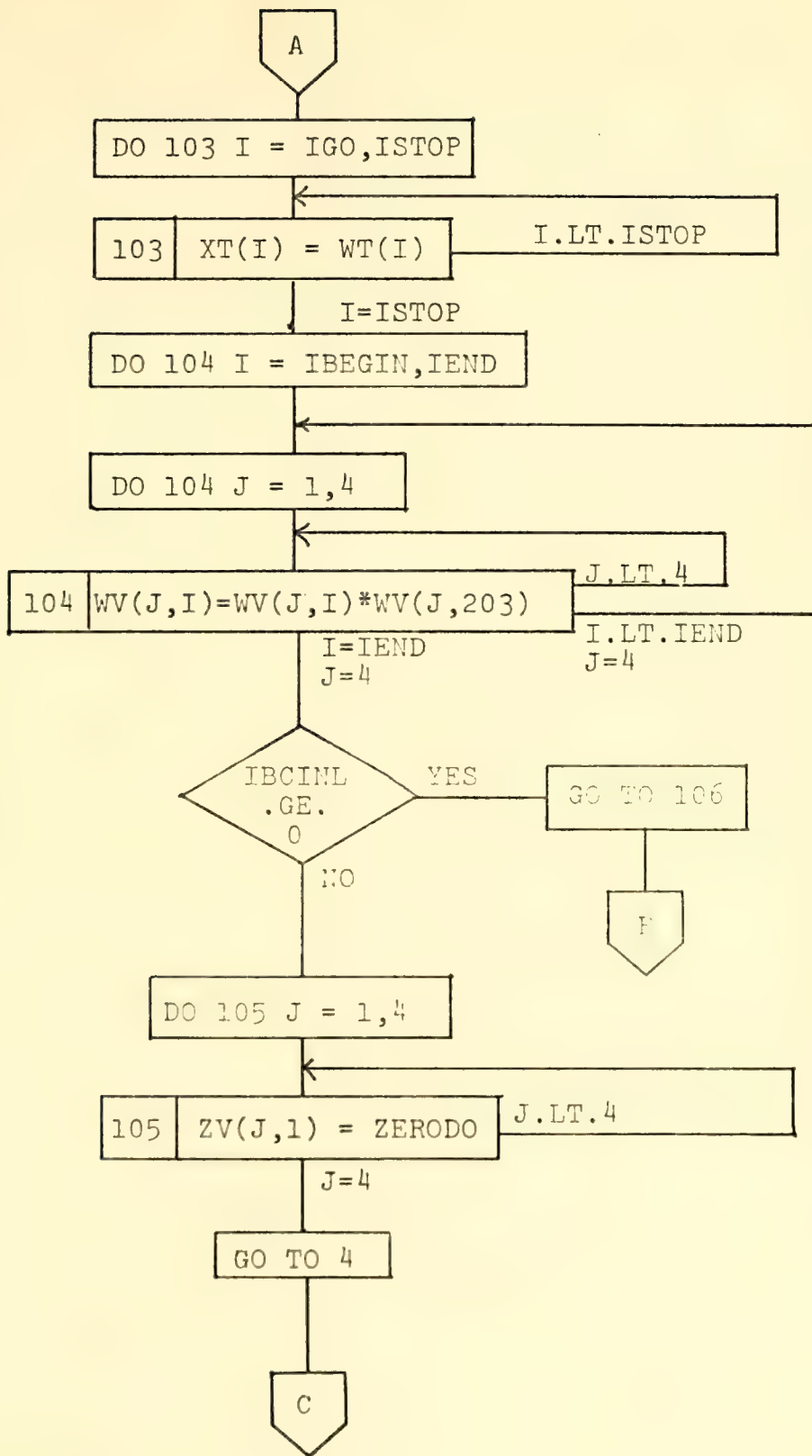


FIGURE 12 continued

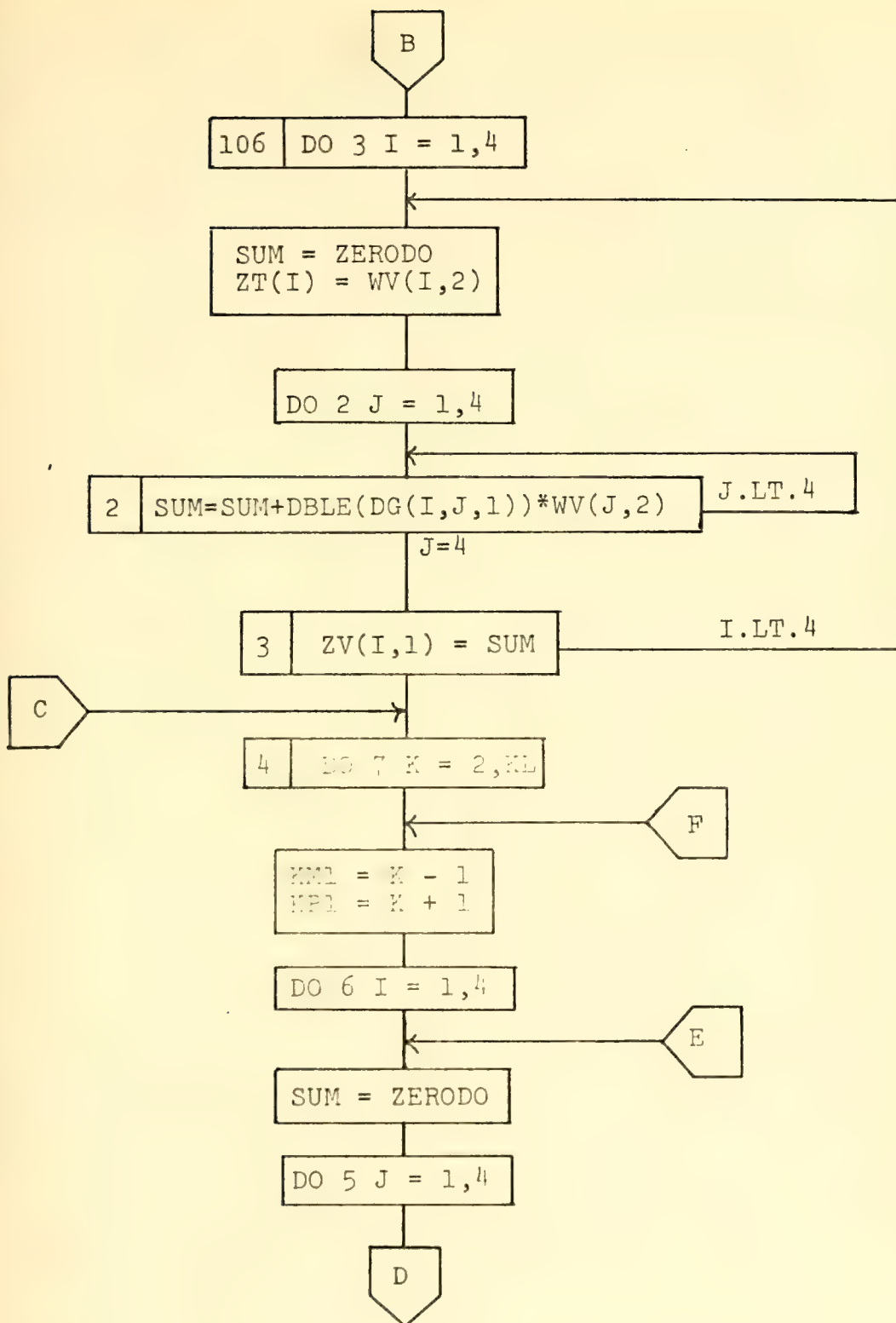


FIGURE 12 continued

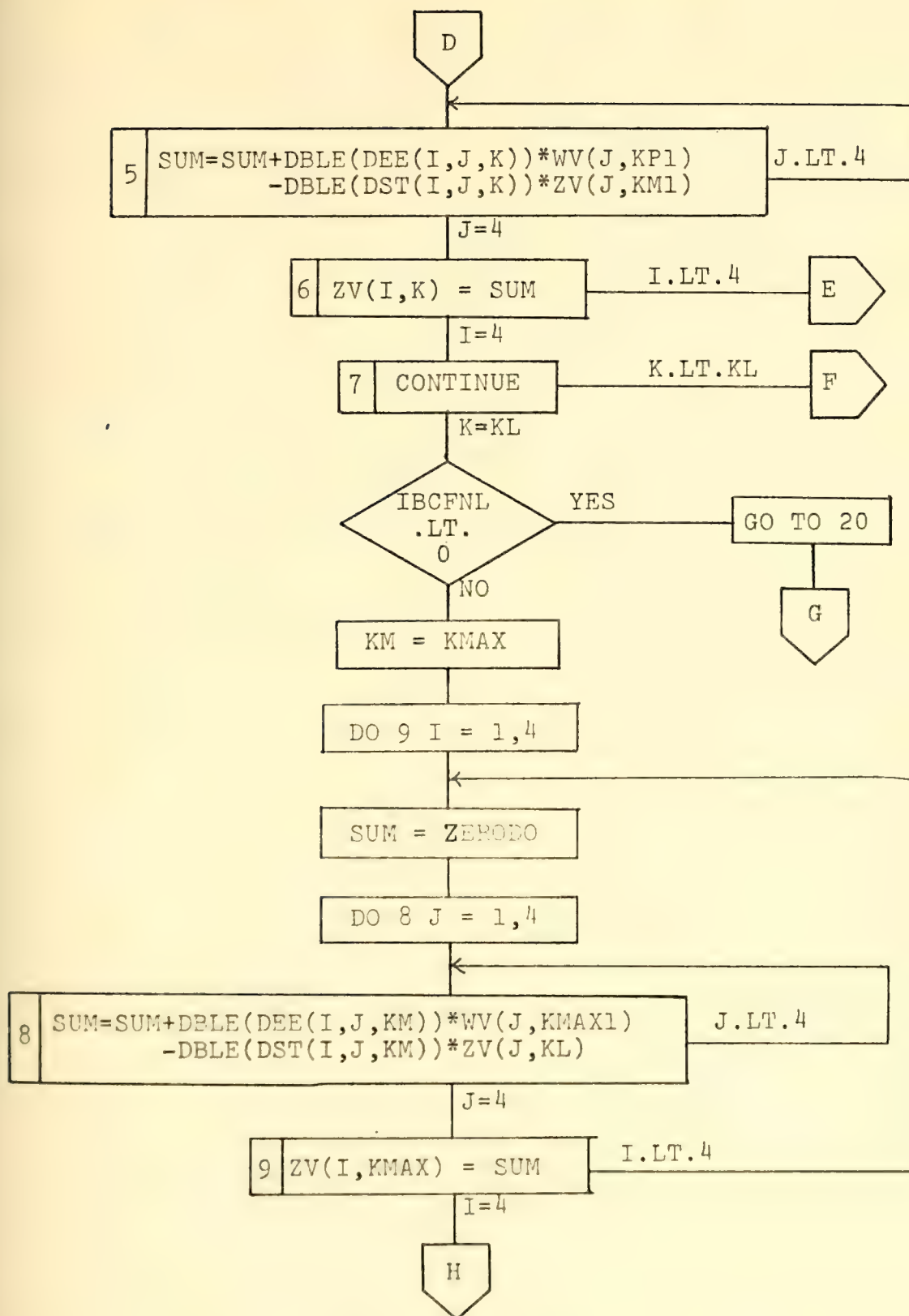


FIGURE 12 continued

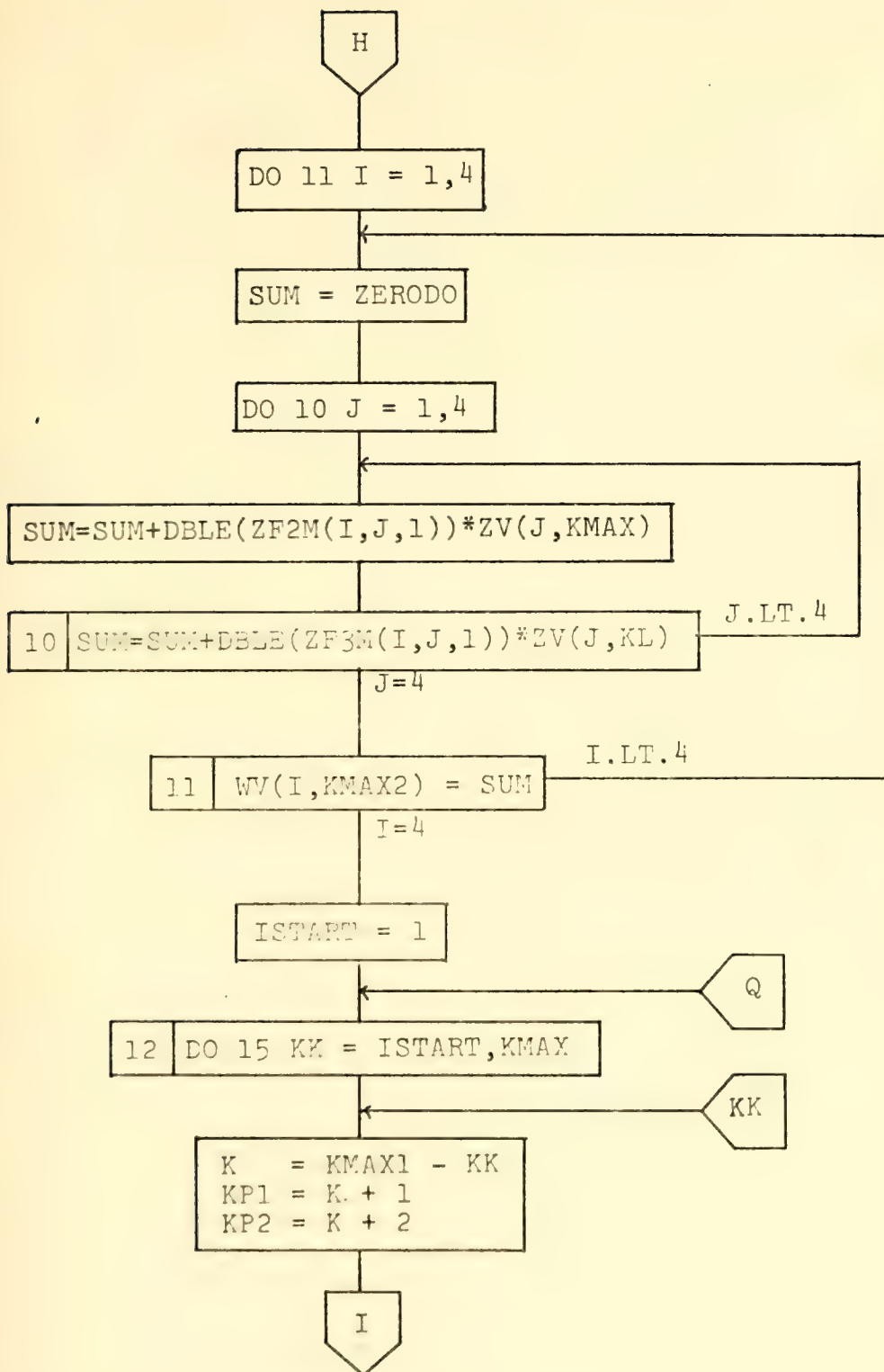


FIGURE 12 continued

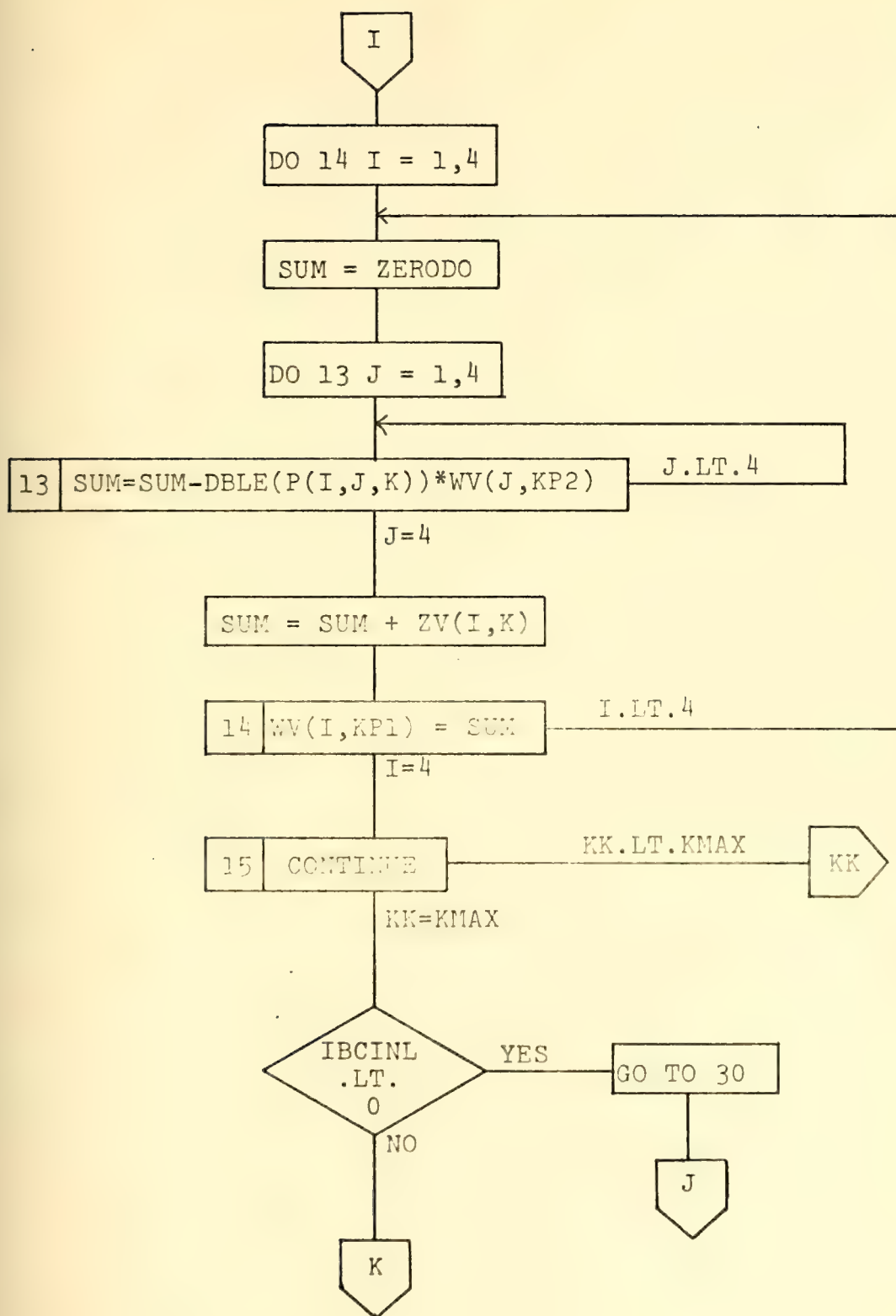


FIGURE 12 continued

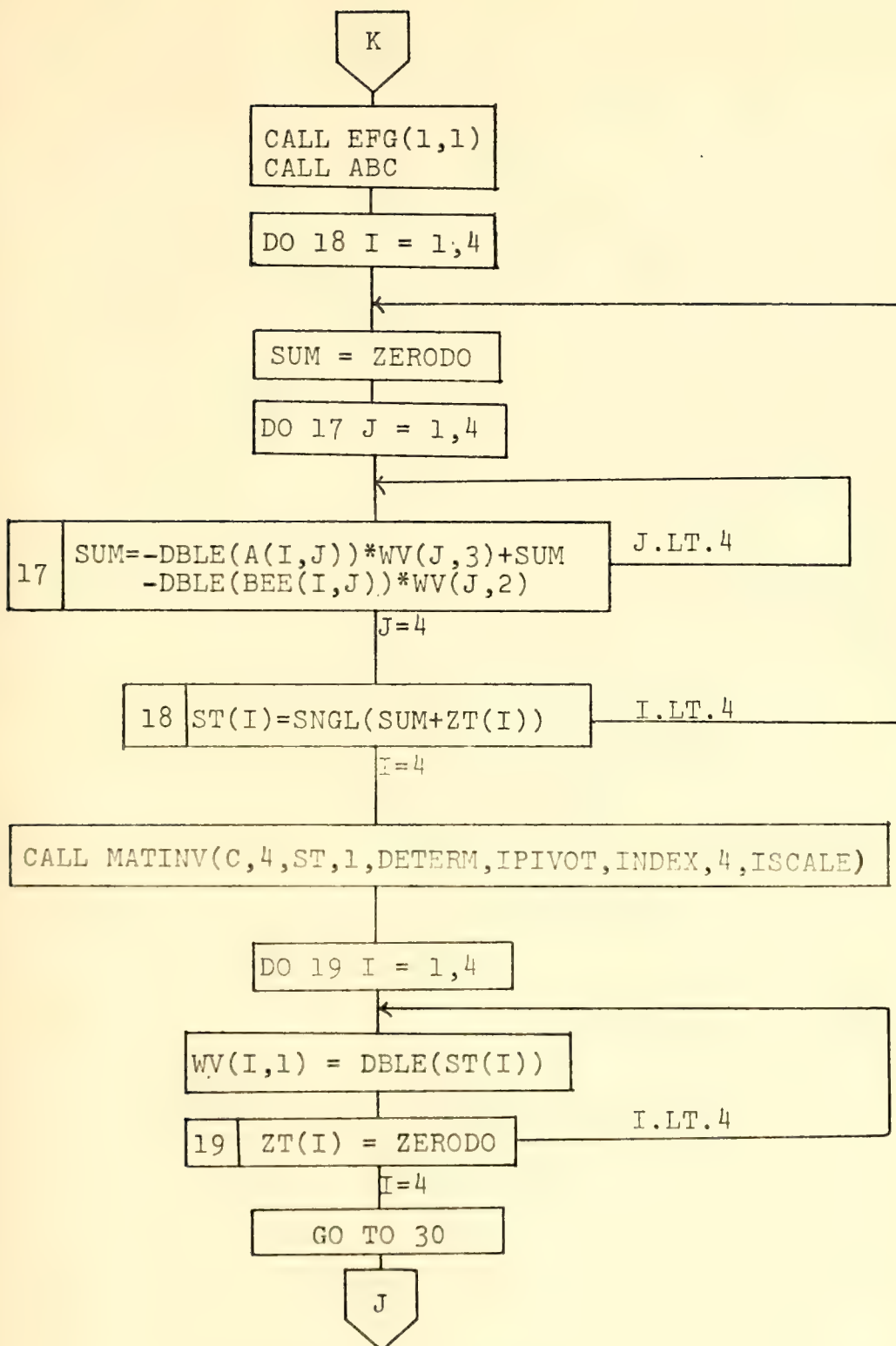


FIGURE 12 continued

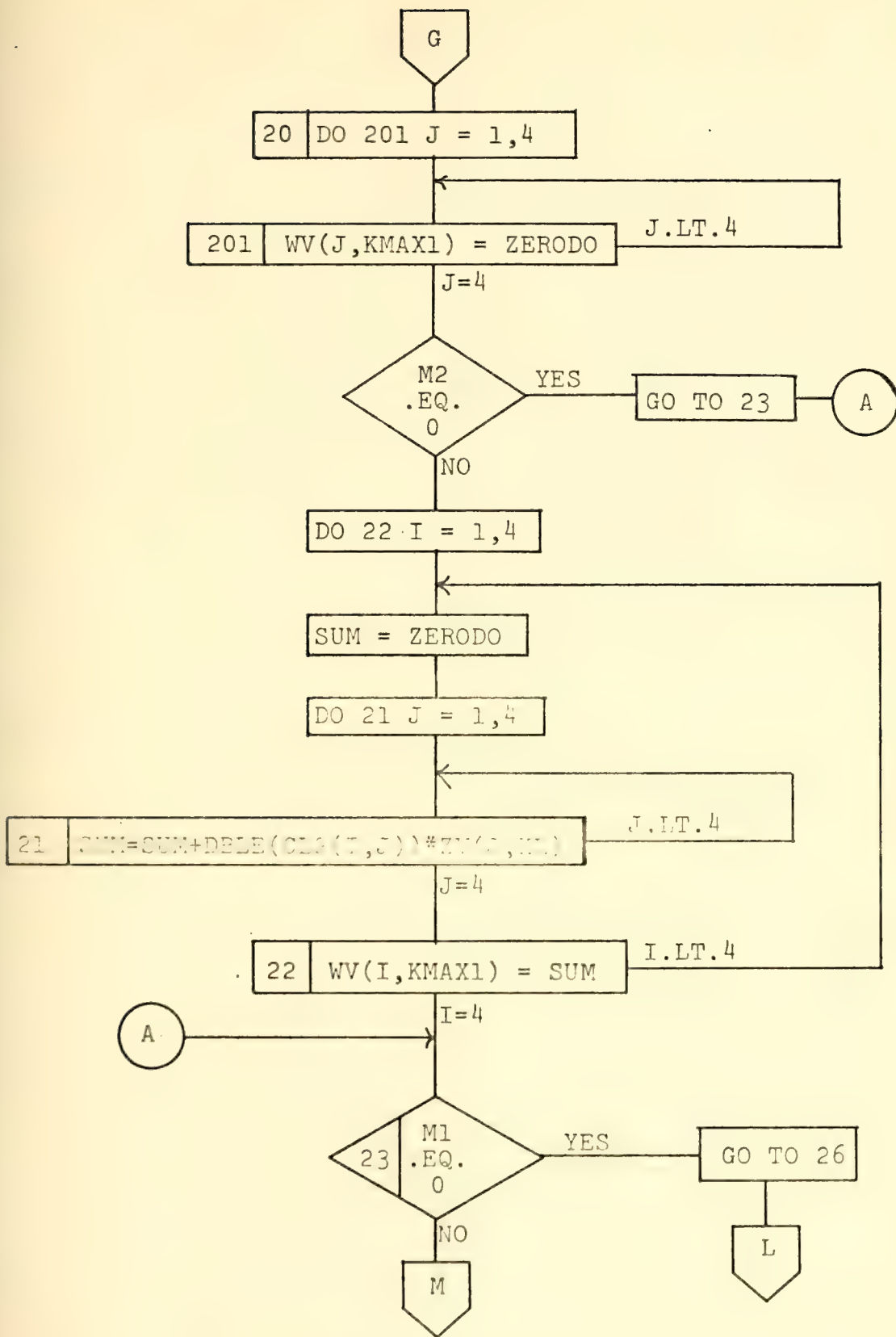


FIGURE 12 continued

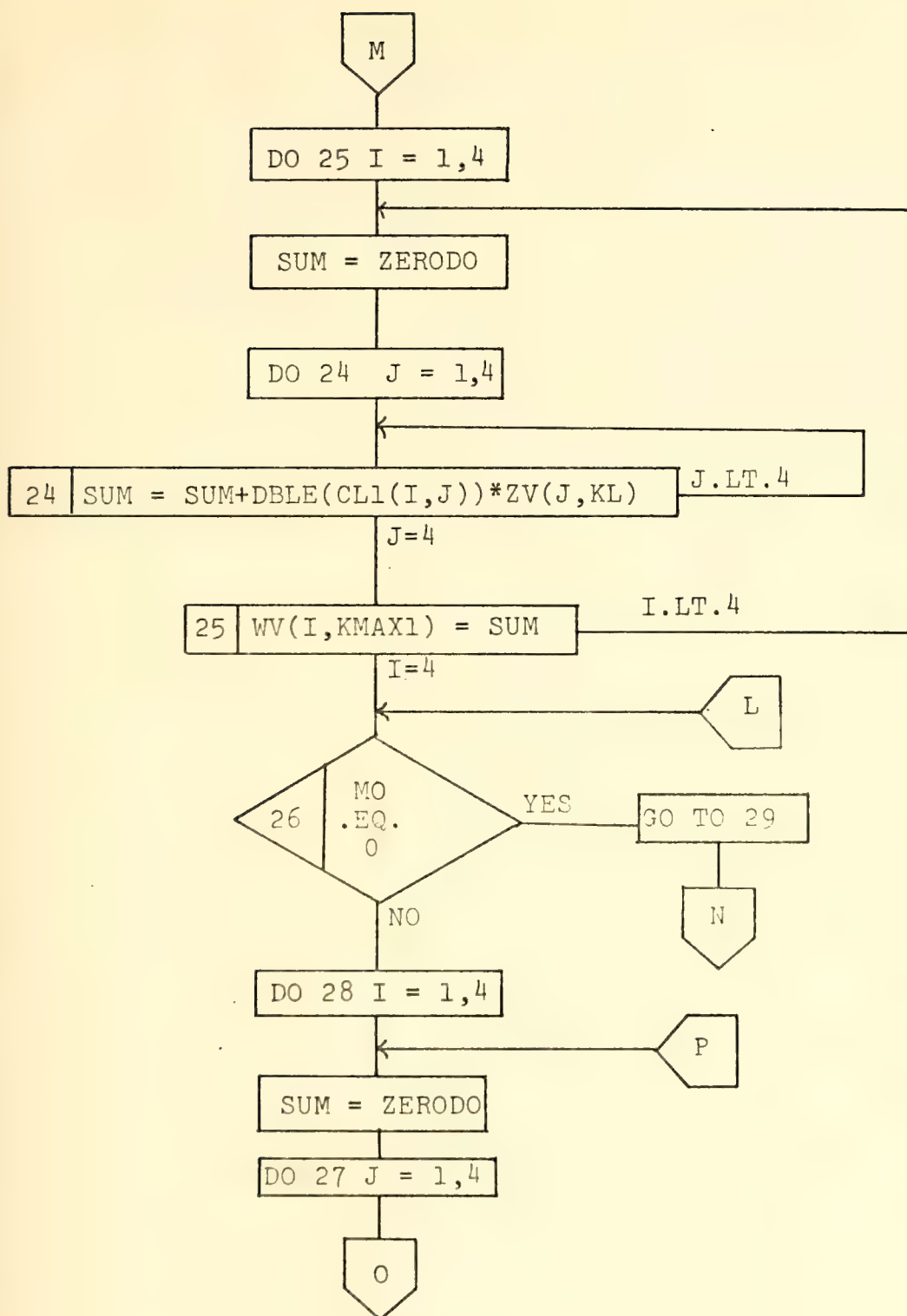


FIGURE 12 continued

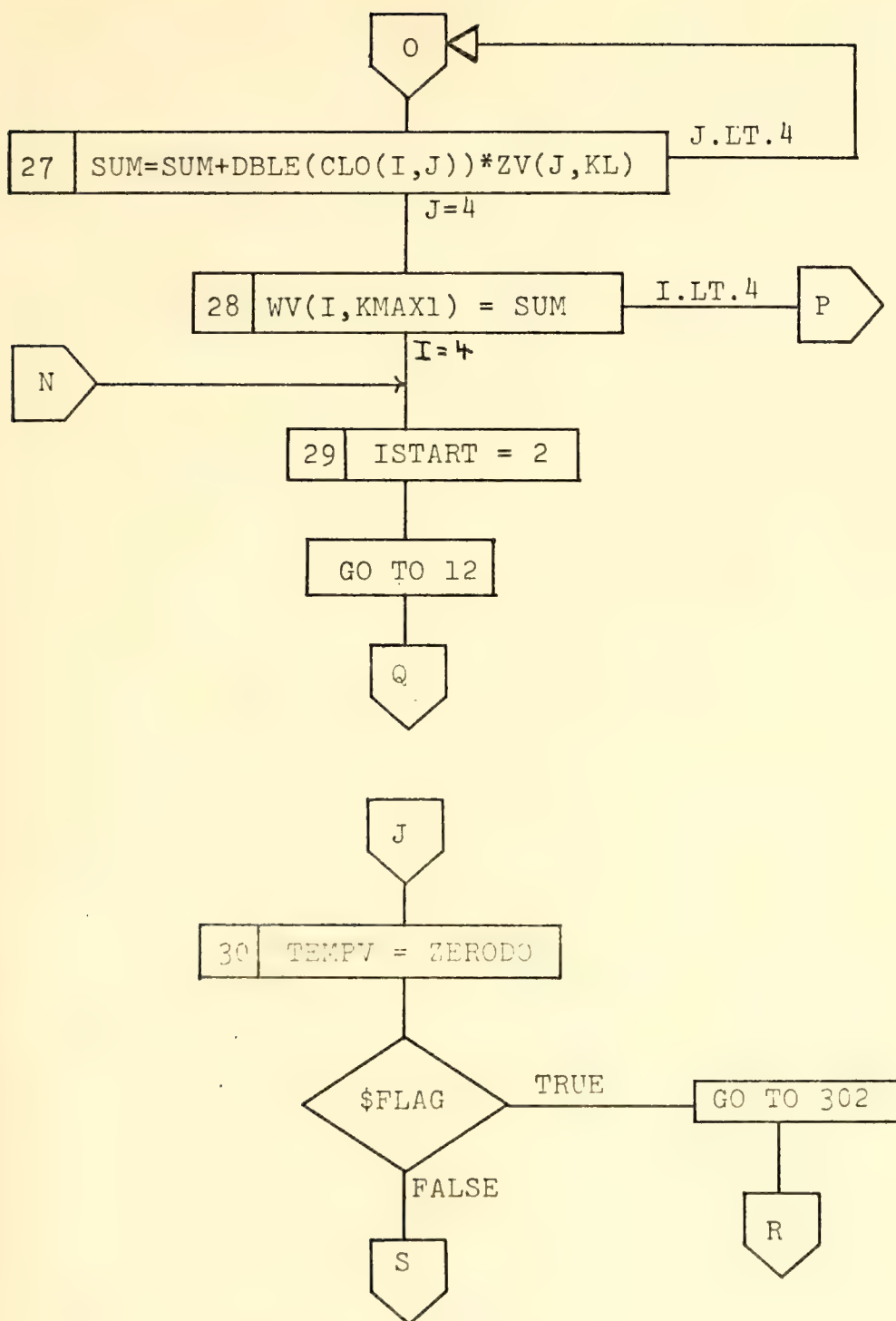


FIGURE 12 continued

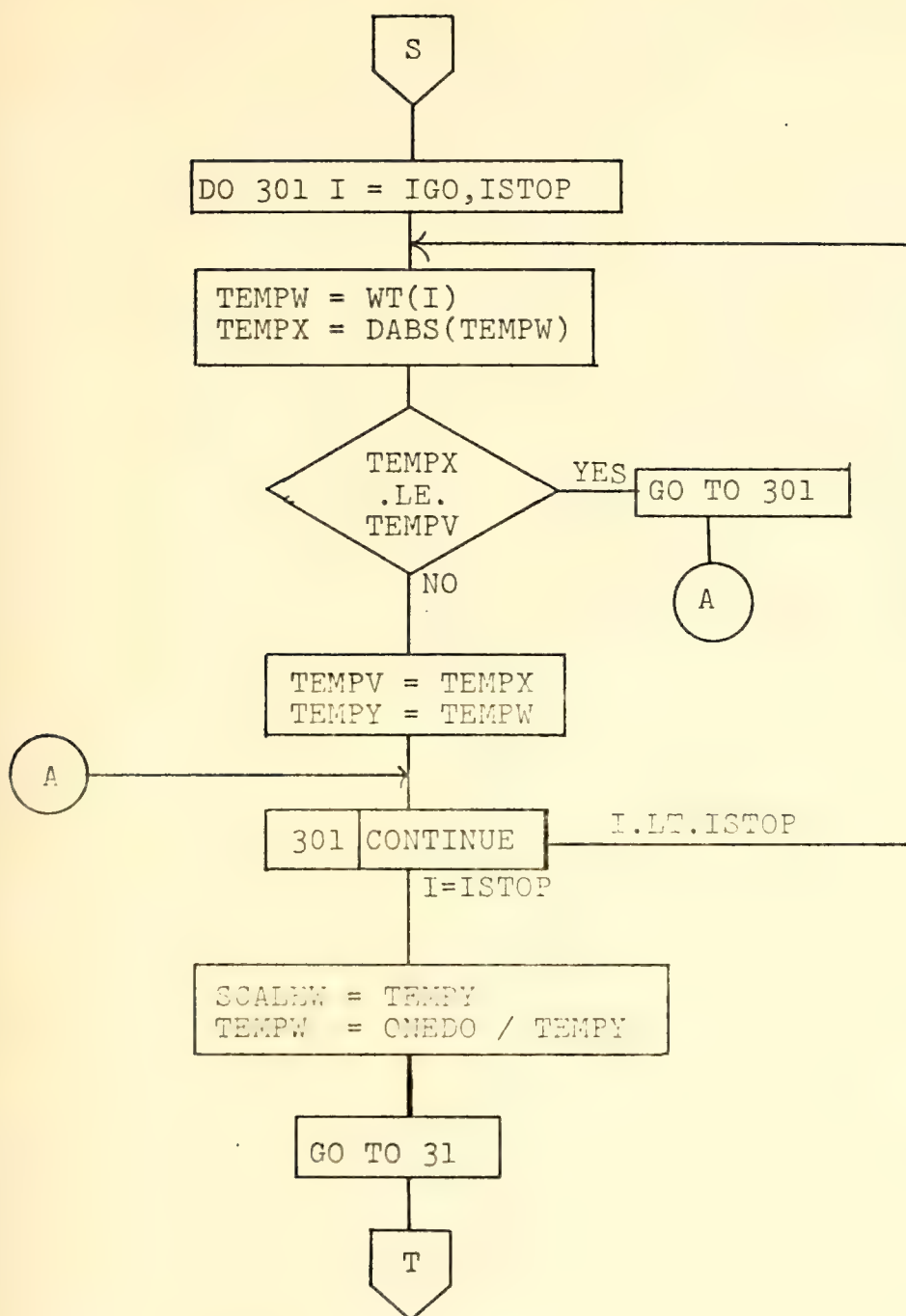


FIGURE 12 continued

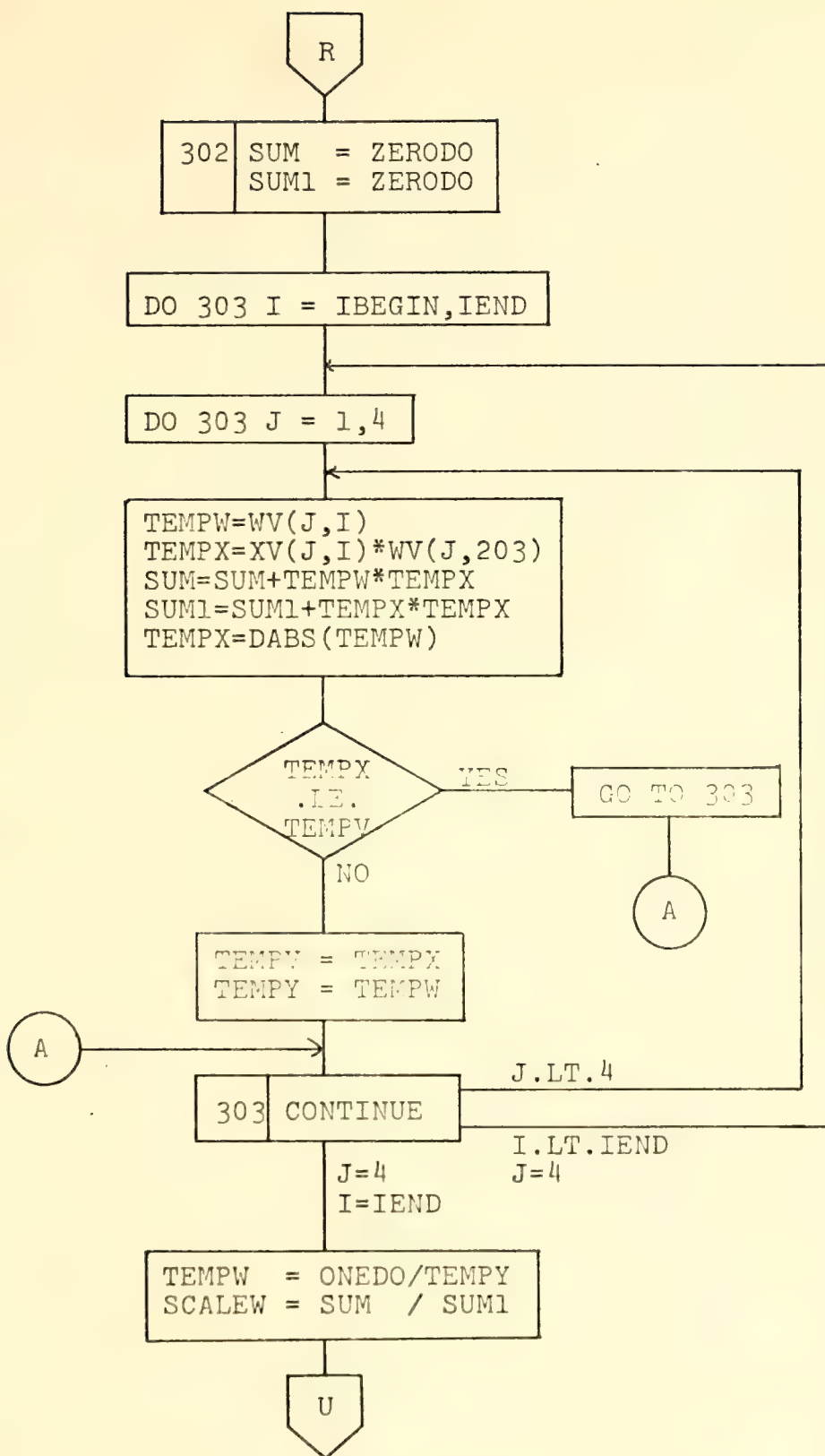


FIGURE 12 continued

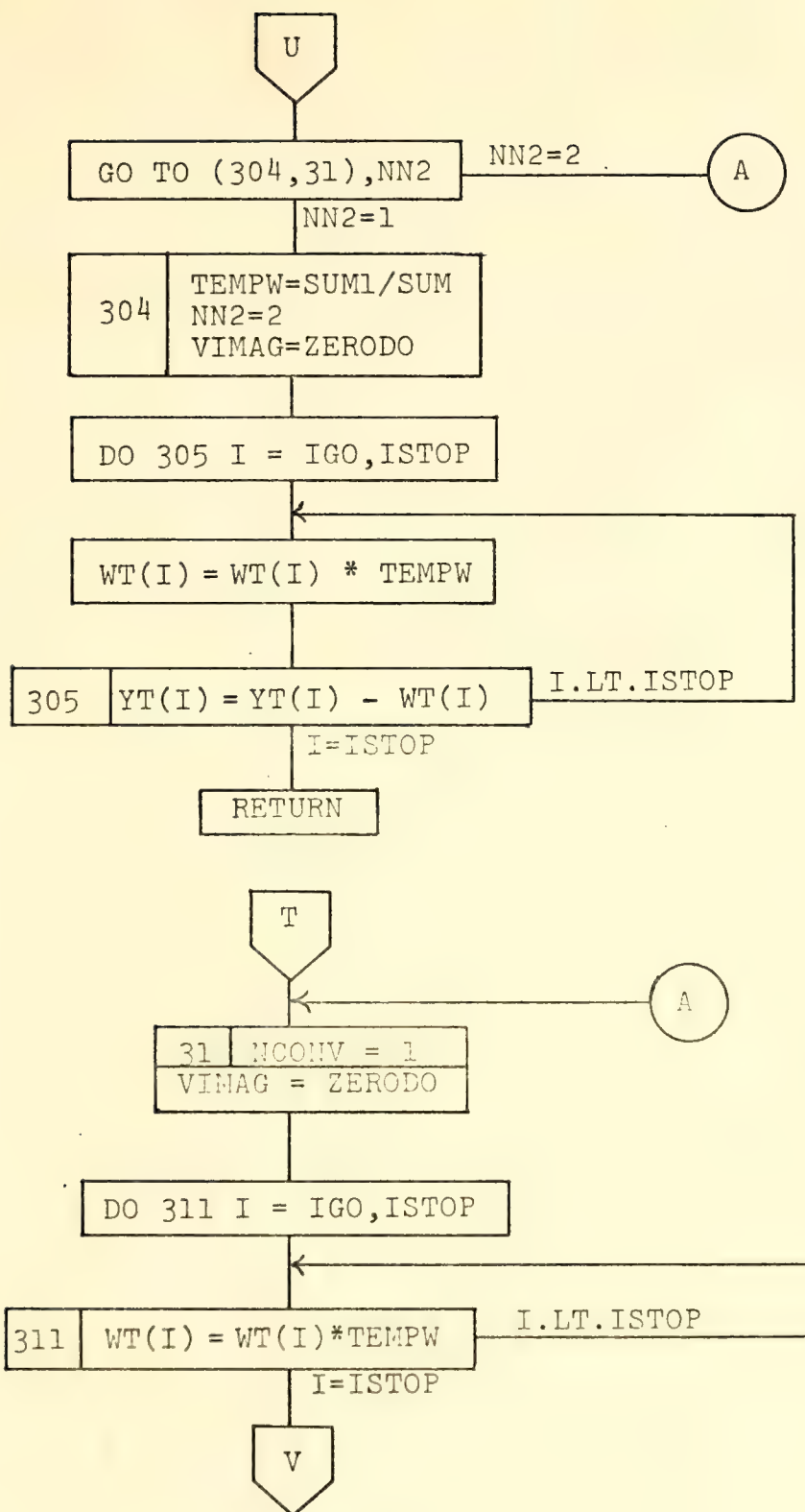


FIGURE 12 continued

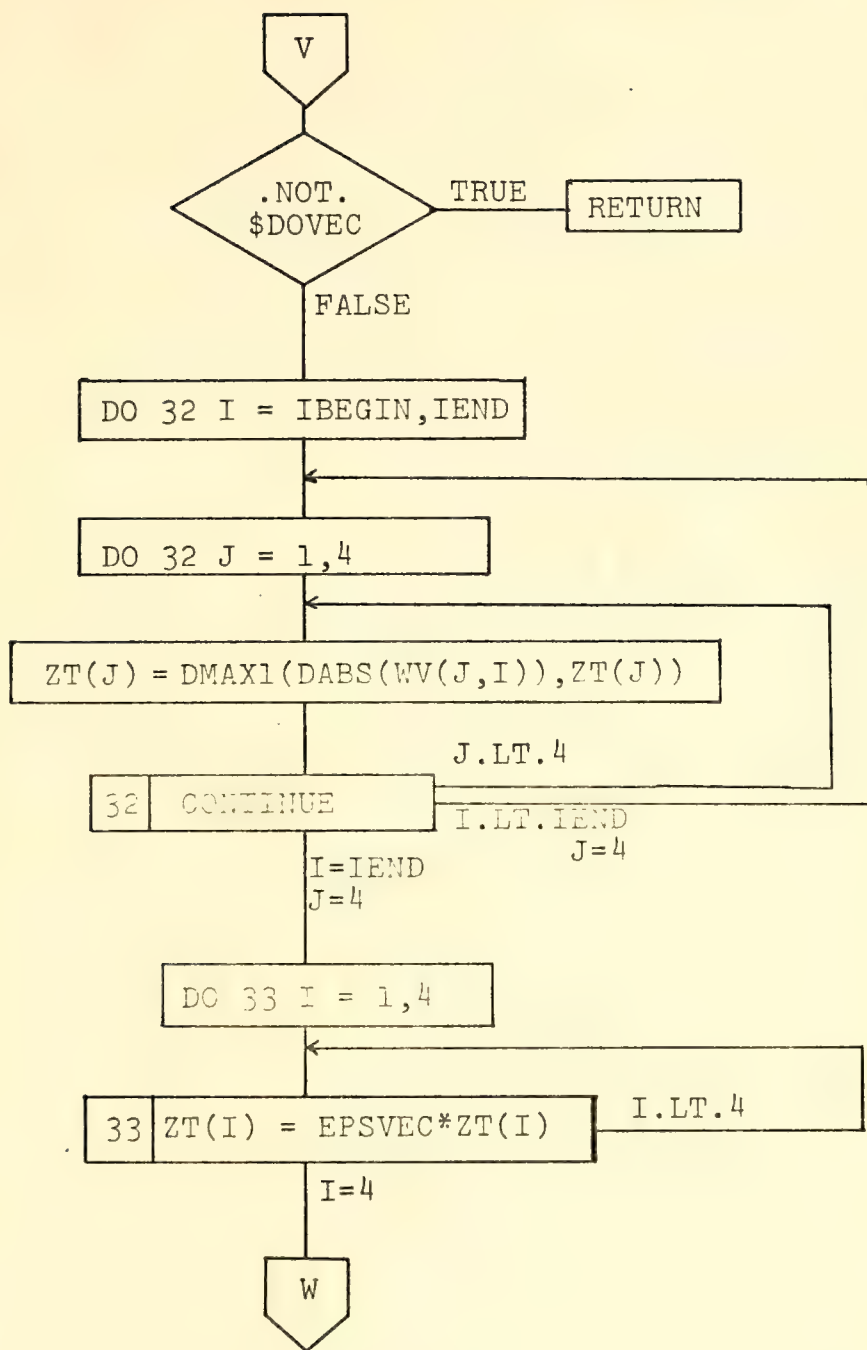


FIGURE 12 continued

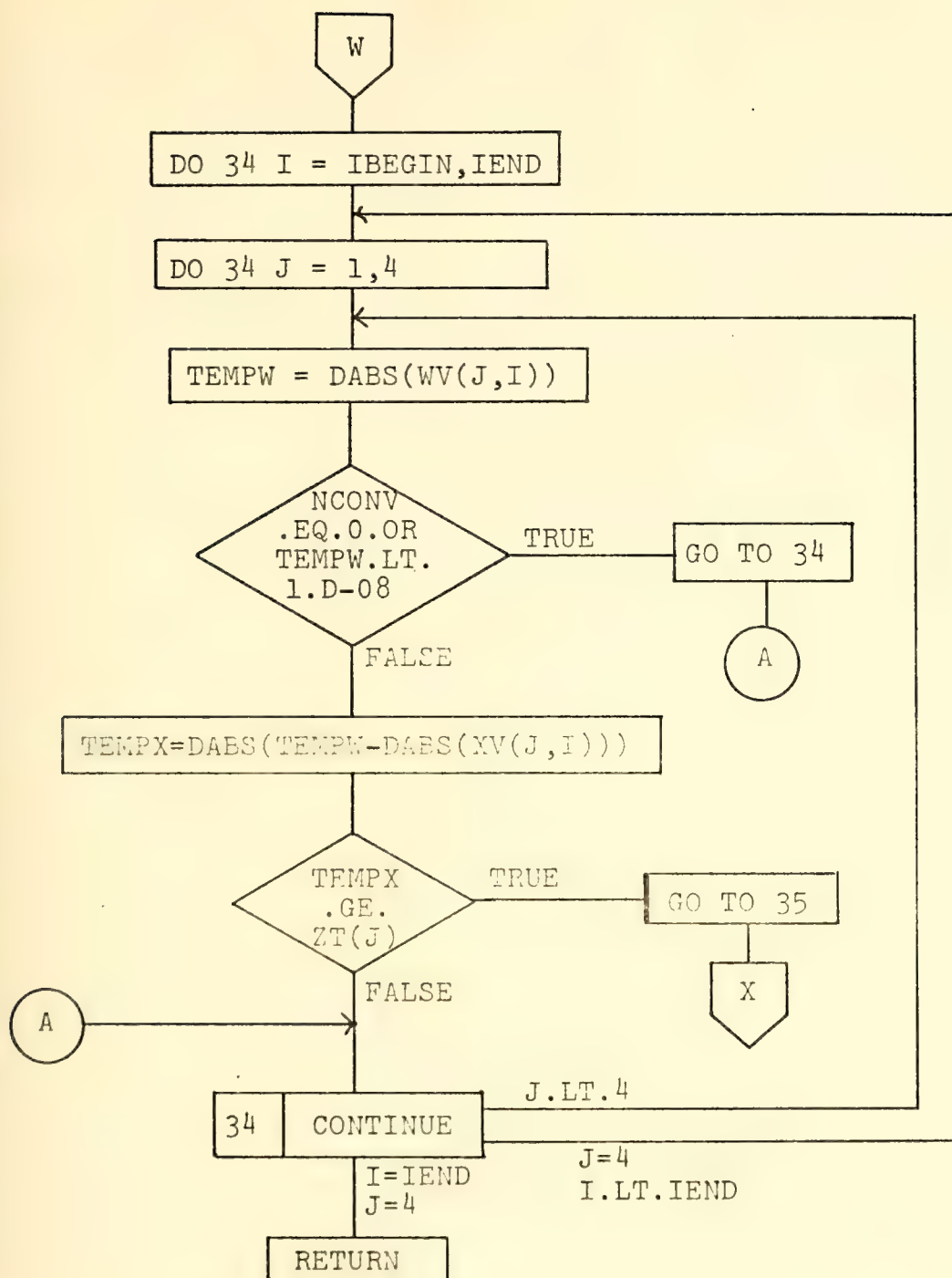


FIGURE 12 continued

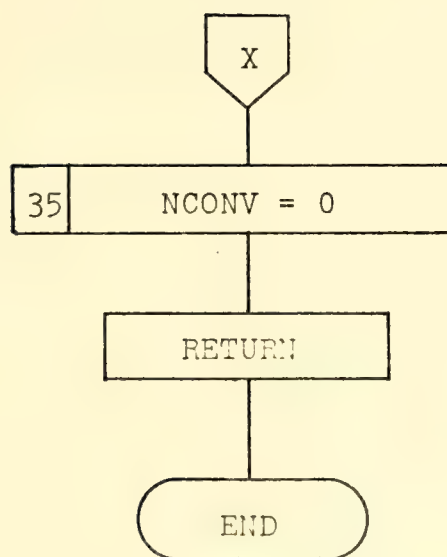


FIGURE 12 continued

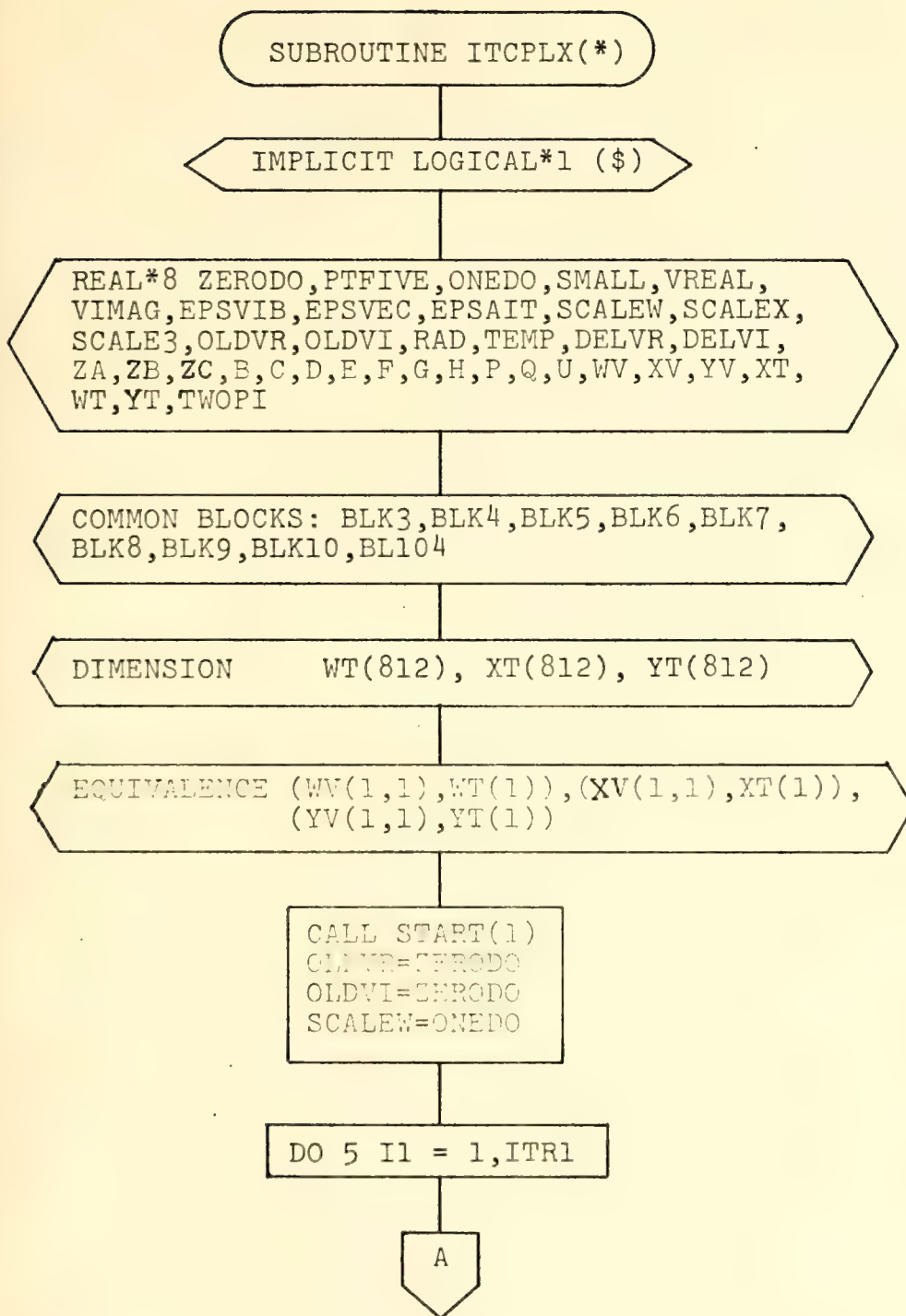


FIGURE 13 SUBROUTINE ITCPLX(*) FLOWCHART

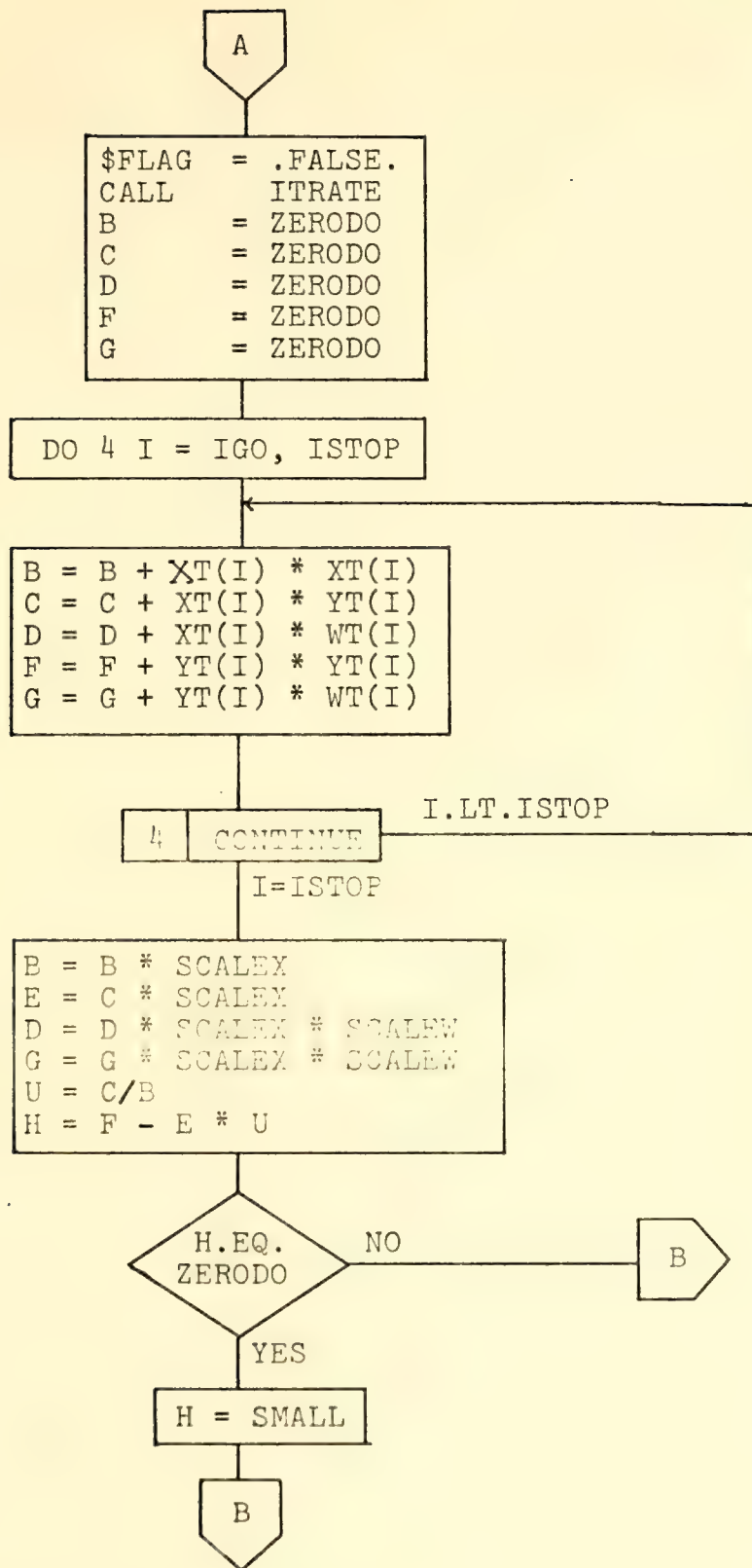


FIGURE 13 continued

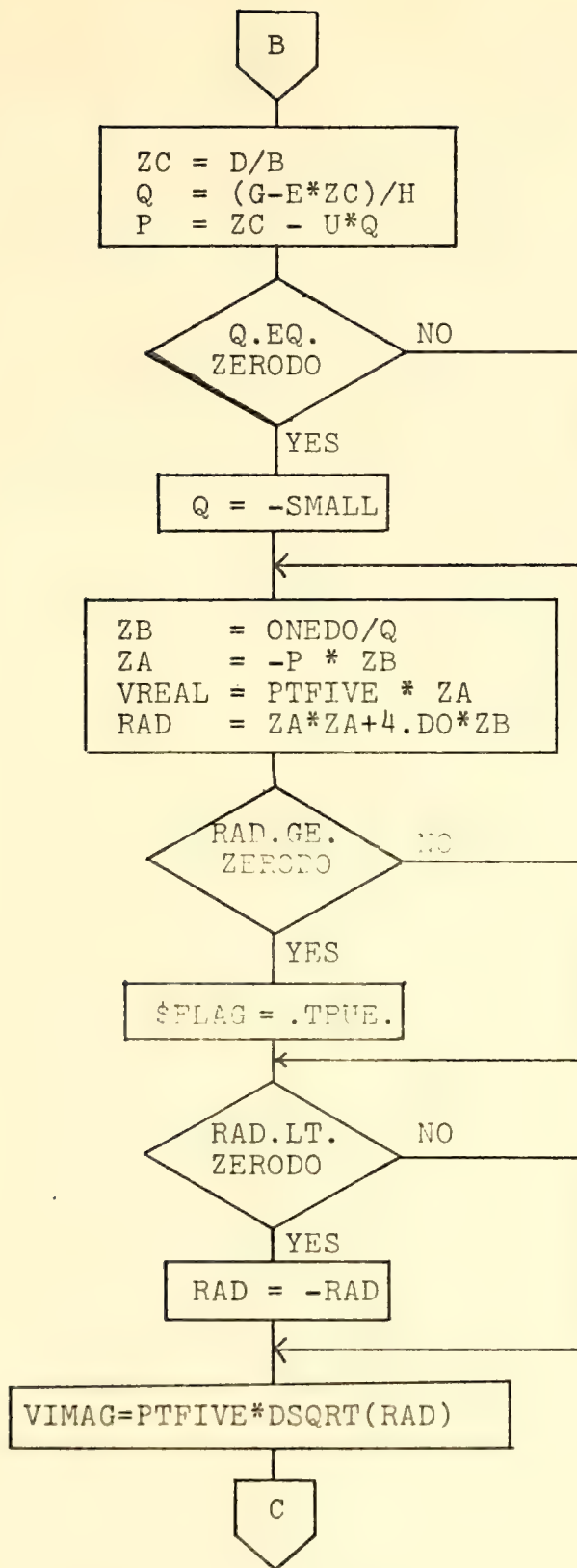


FIGURE 13 continued

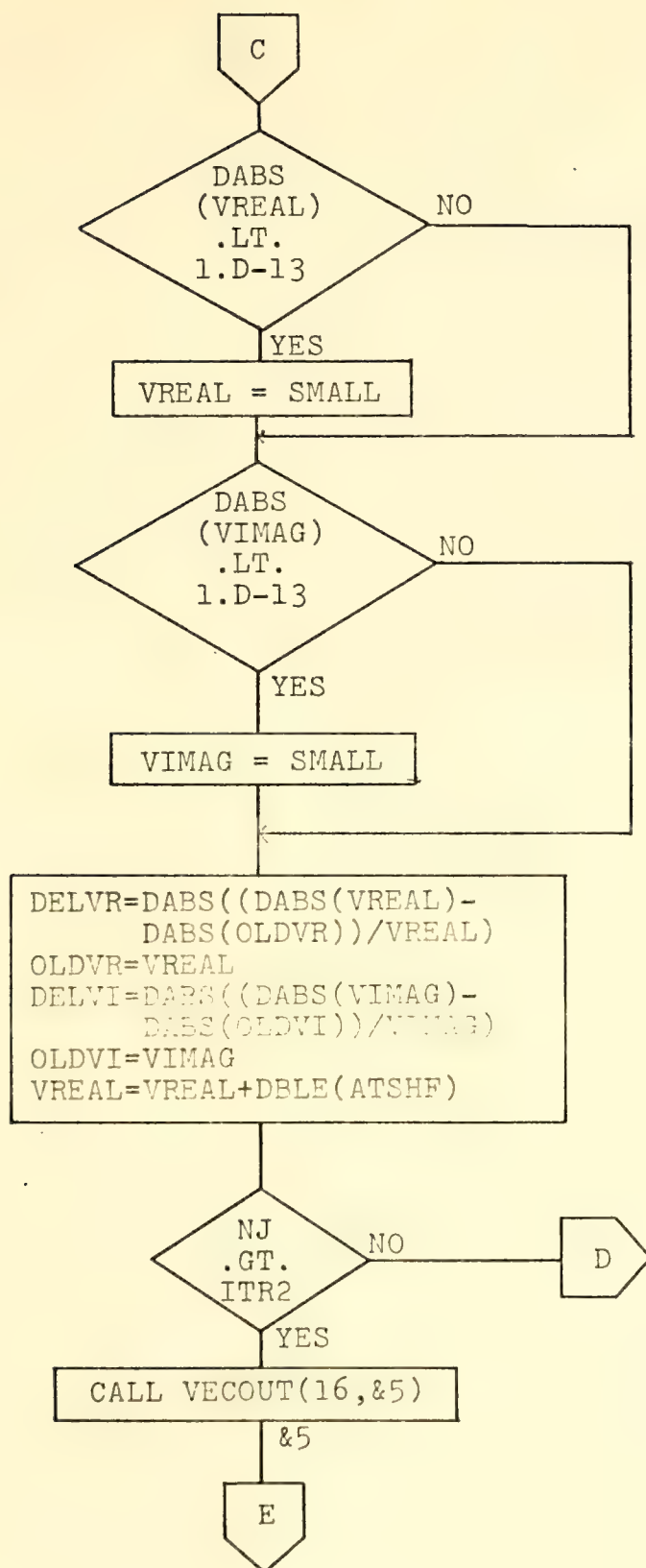


FIGURE 13 continued

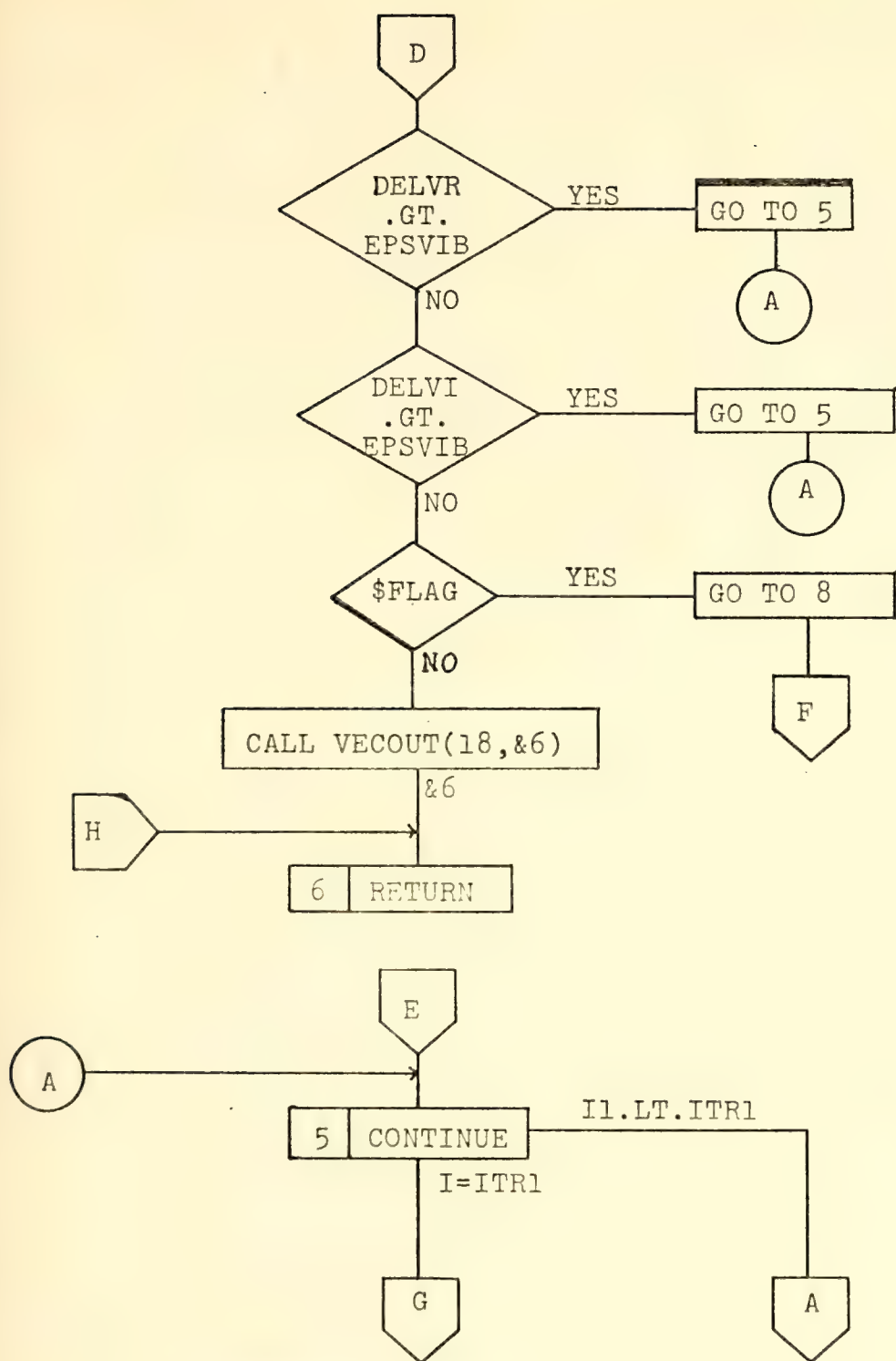


FIGURE 13 continued

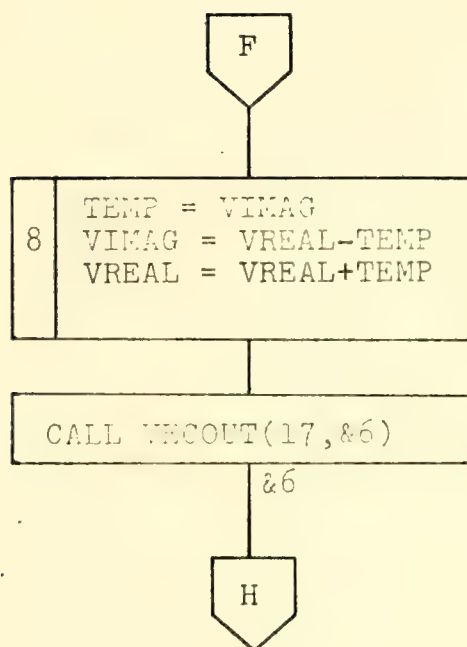
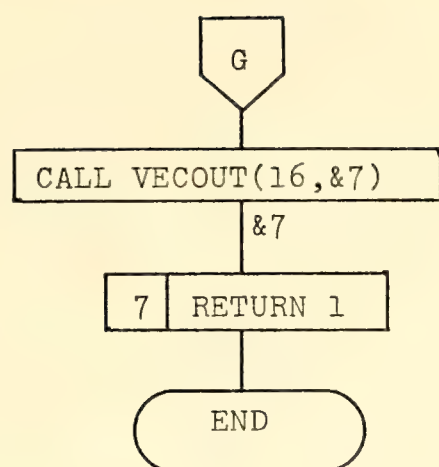


FIGURE 13 continued

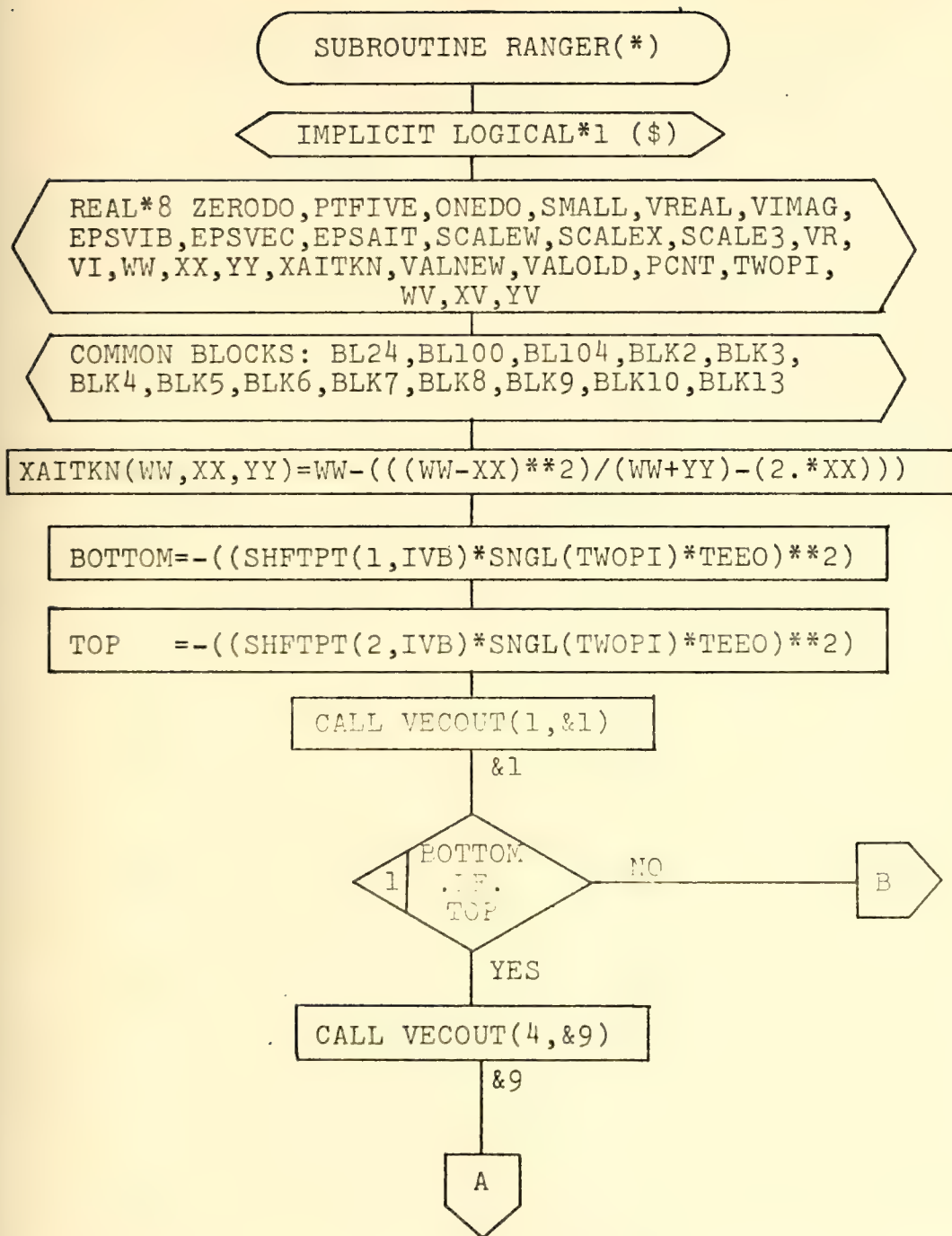


FIGURE 14. SUBROUTINE RANGER(*) FLOWCHART

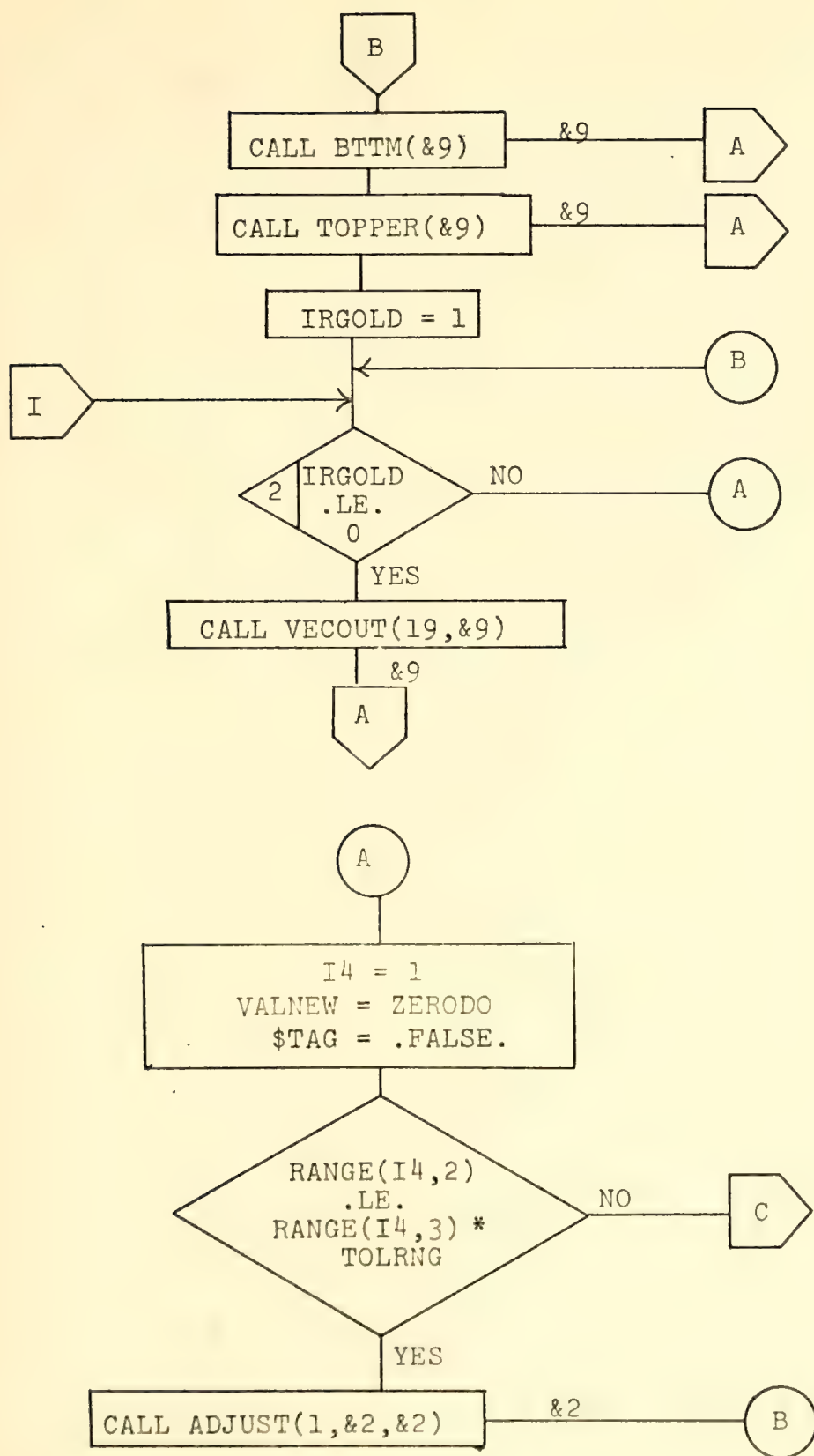


FIGURE 14 continued

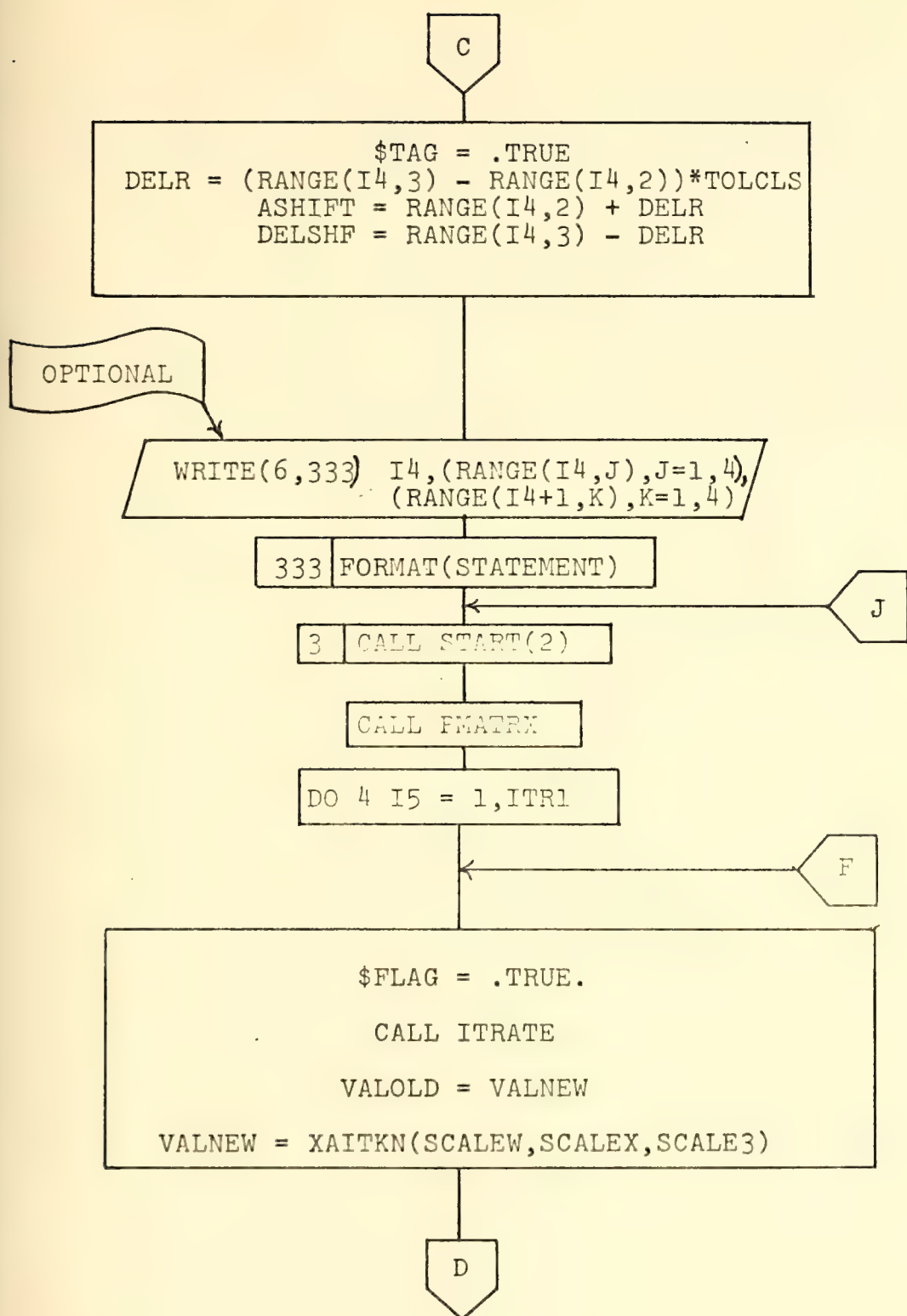


FIGURE 14 continued

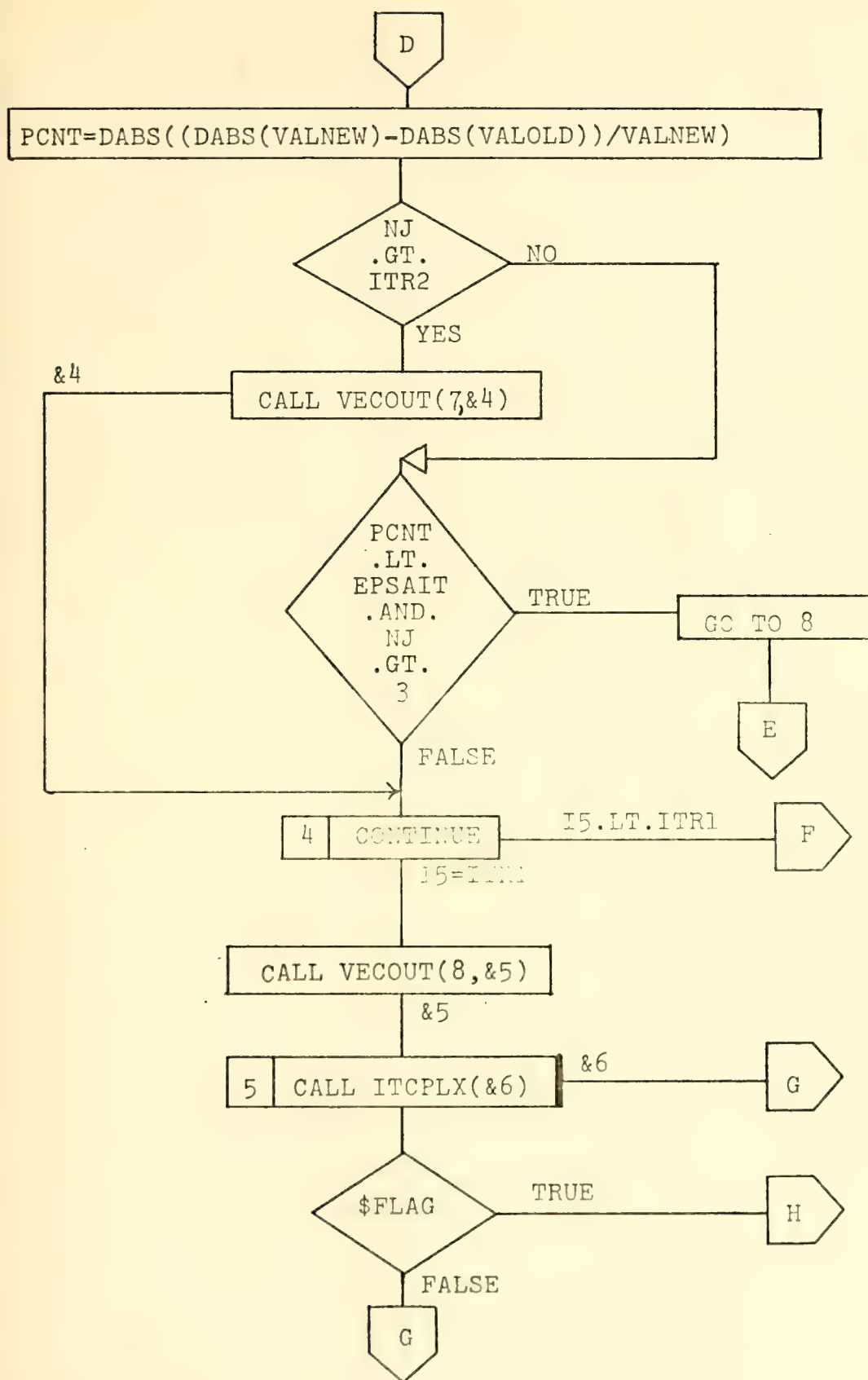


FIGURE 14 continued

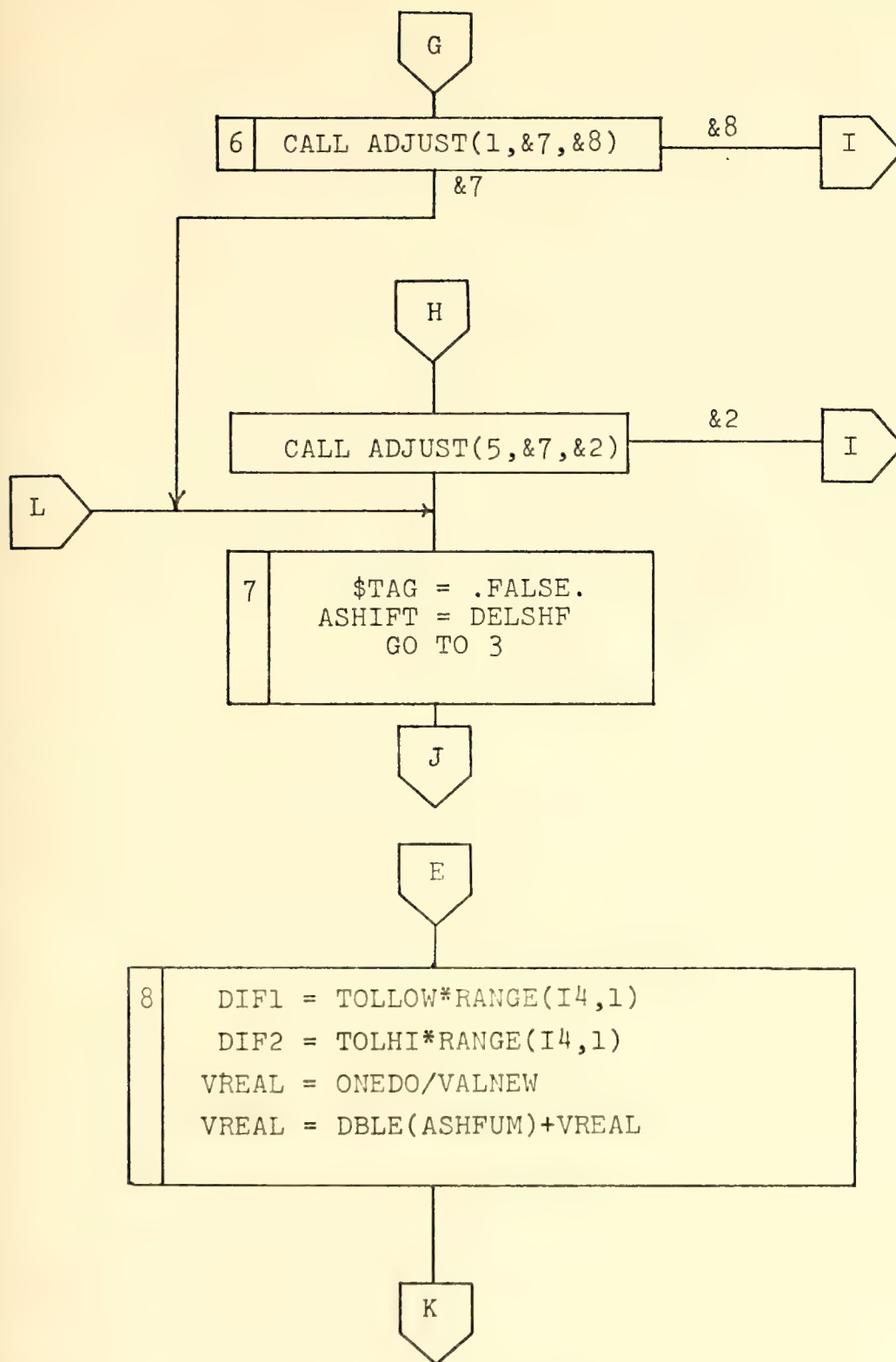


FIGURE 14 continued

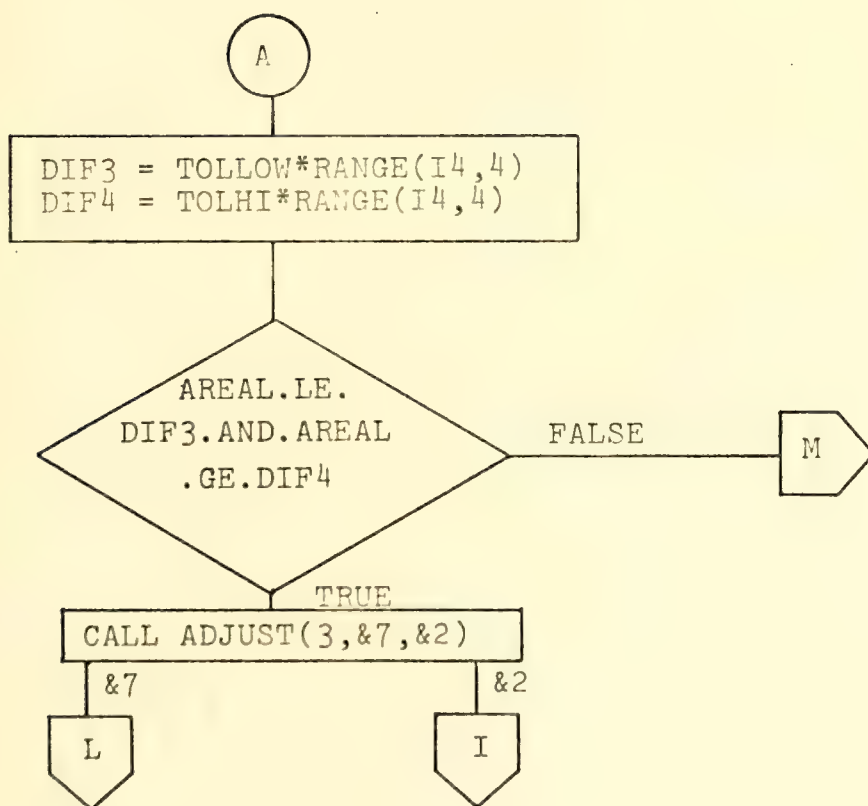
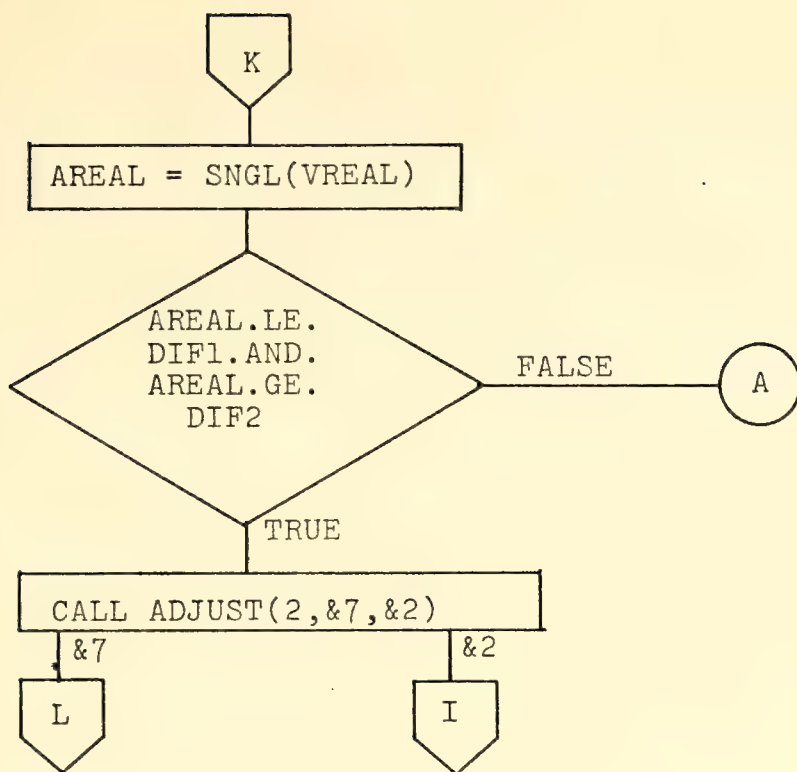


FIGURE 14 continued

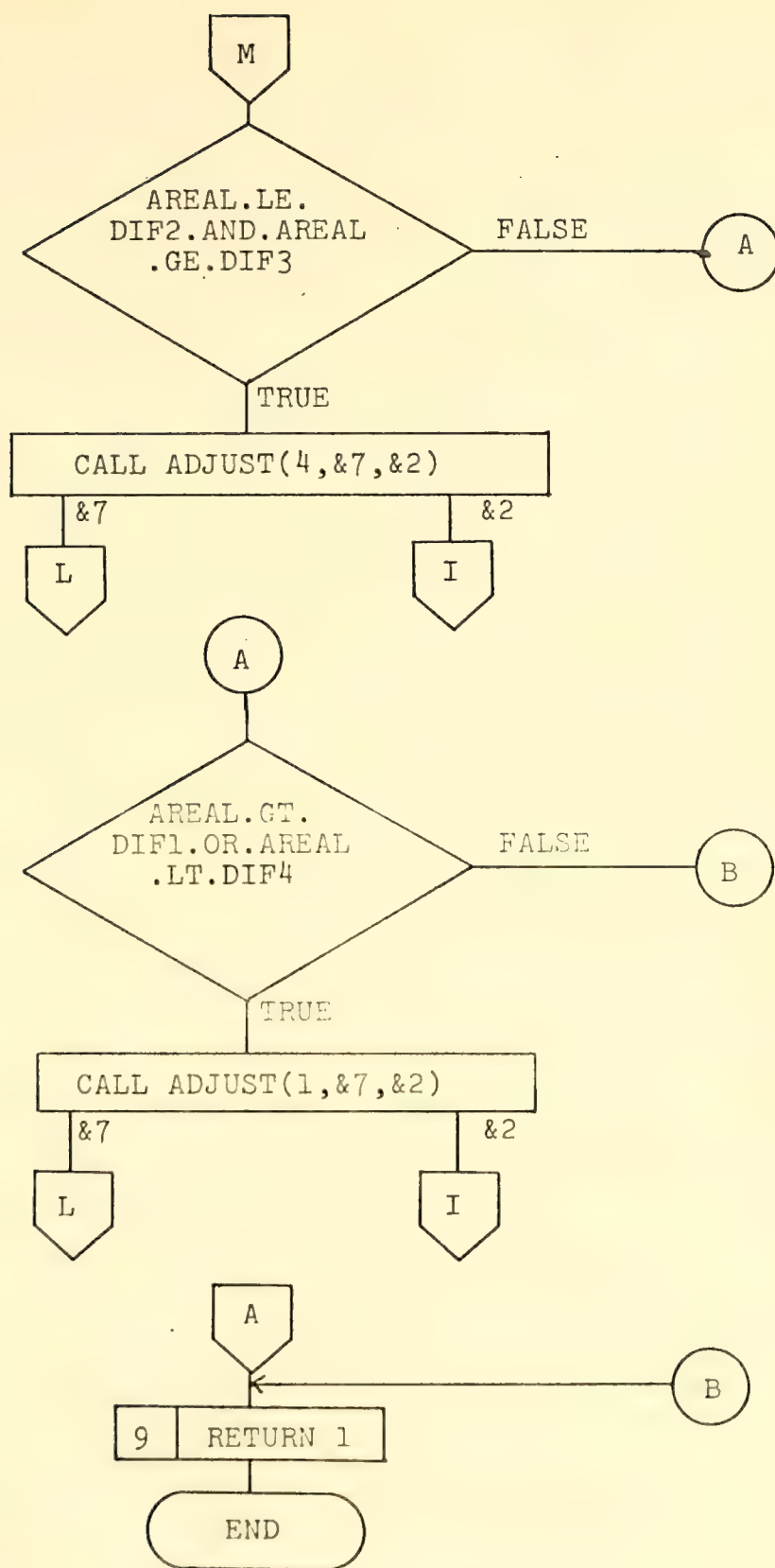


FIGURE 14 continued

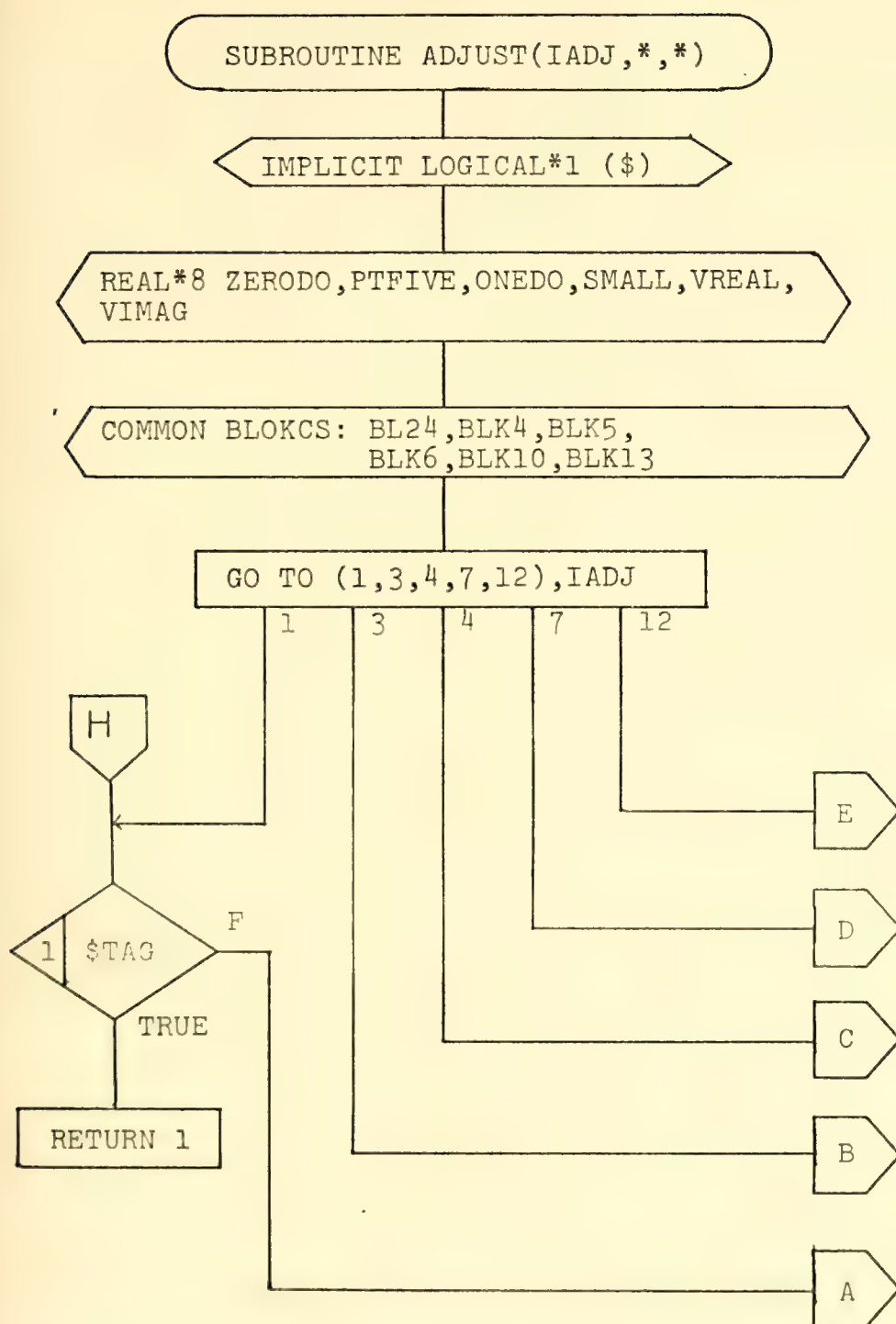


FIGURE 15. SUBROUTINE ADJUST(IADJ,*,*) FLOWCHART

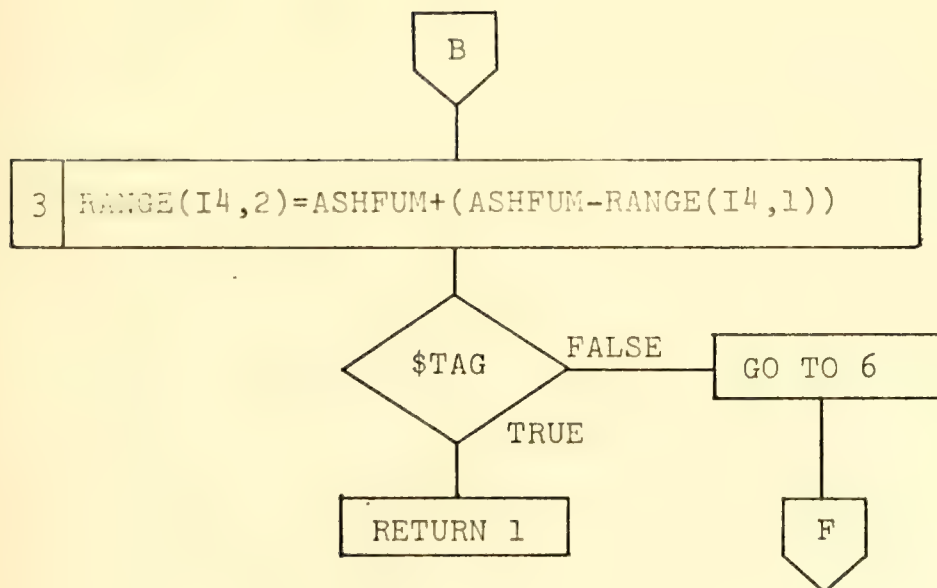
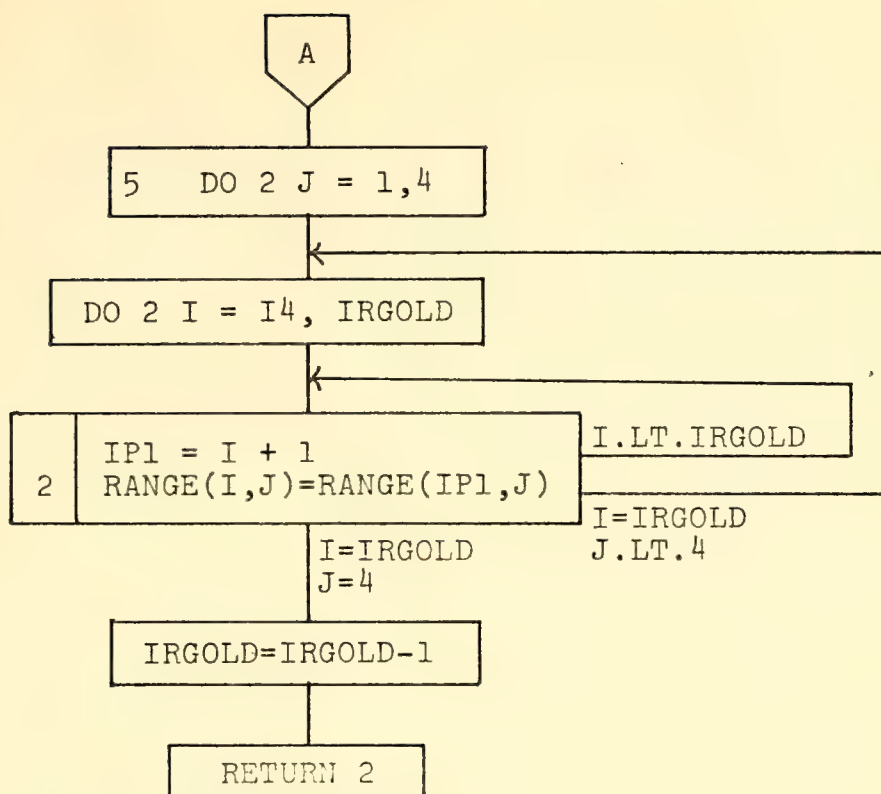


FIGURE 15 continued

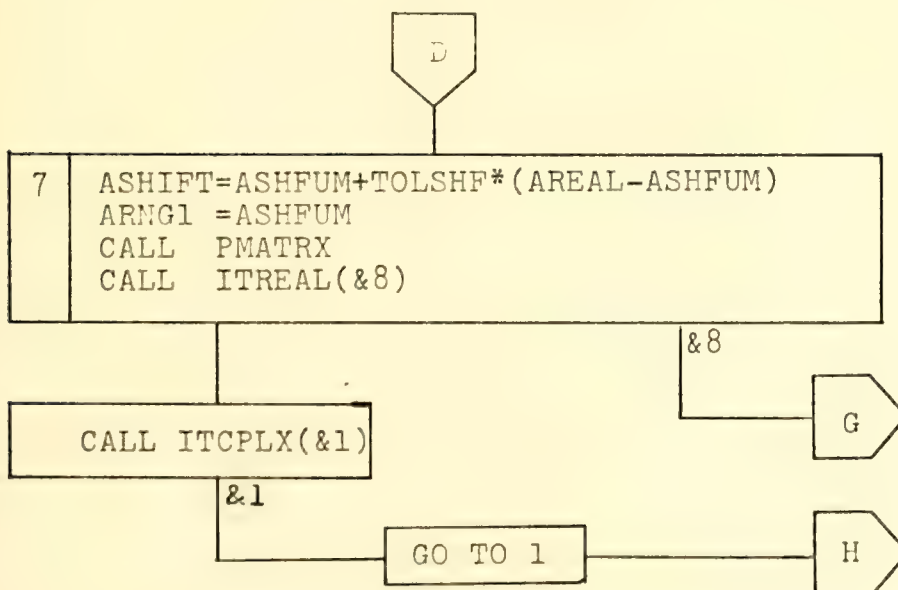
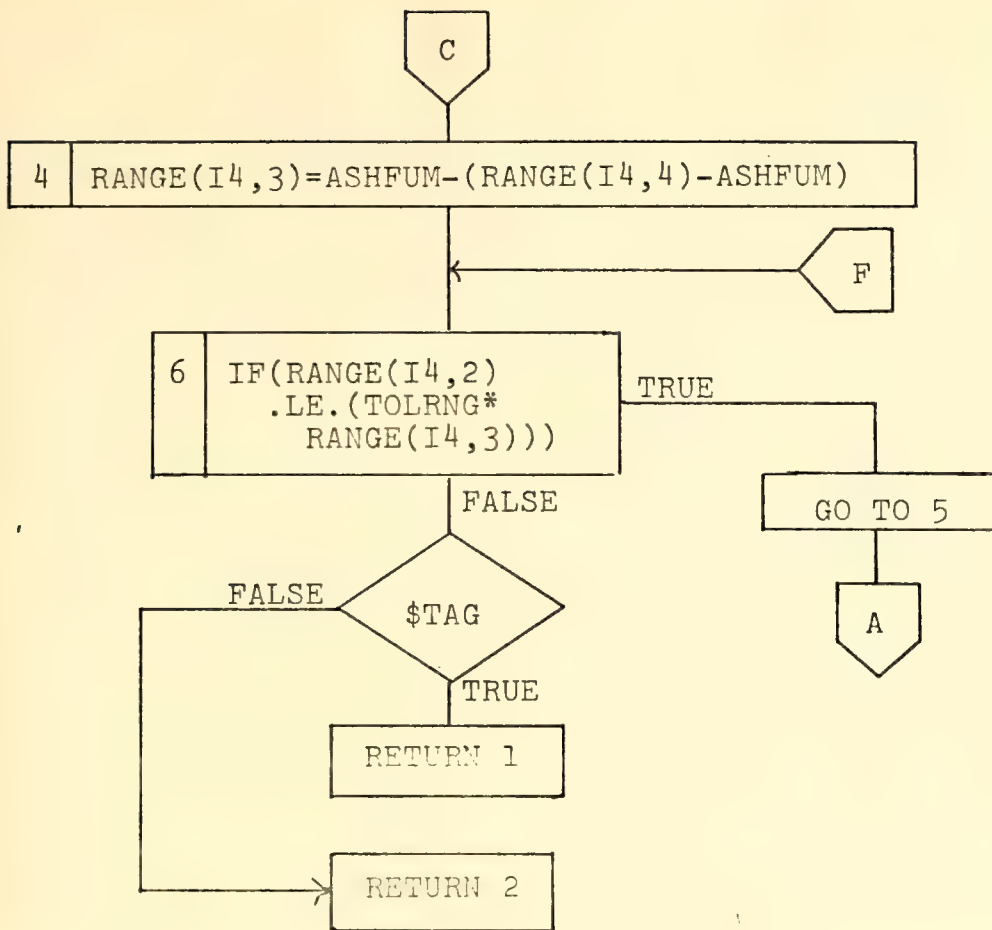


FIGURE 15 continued

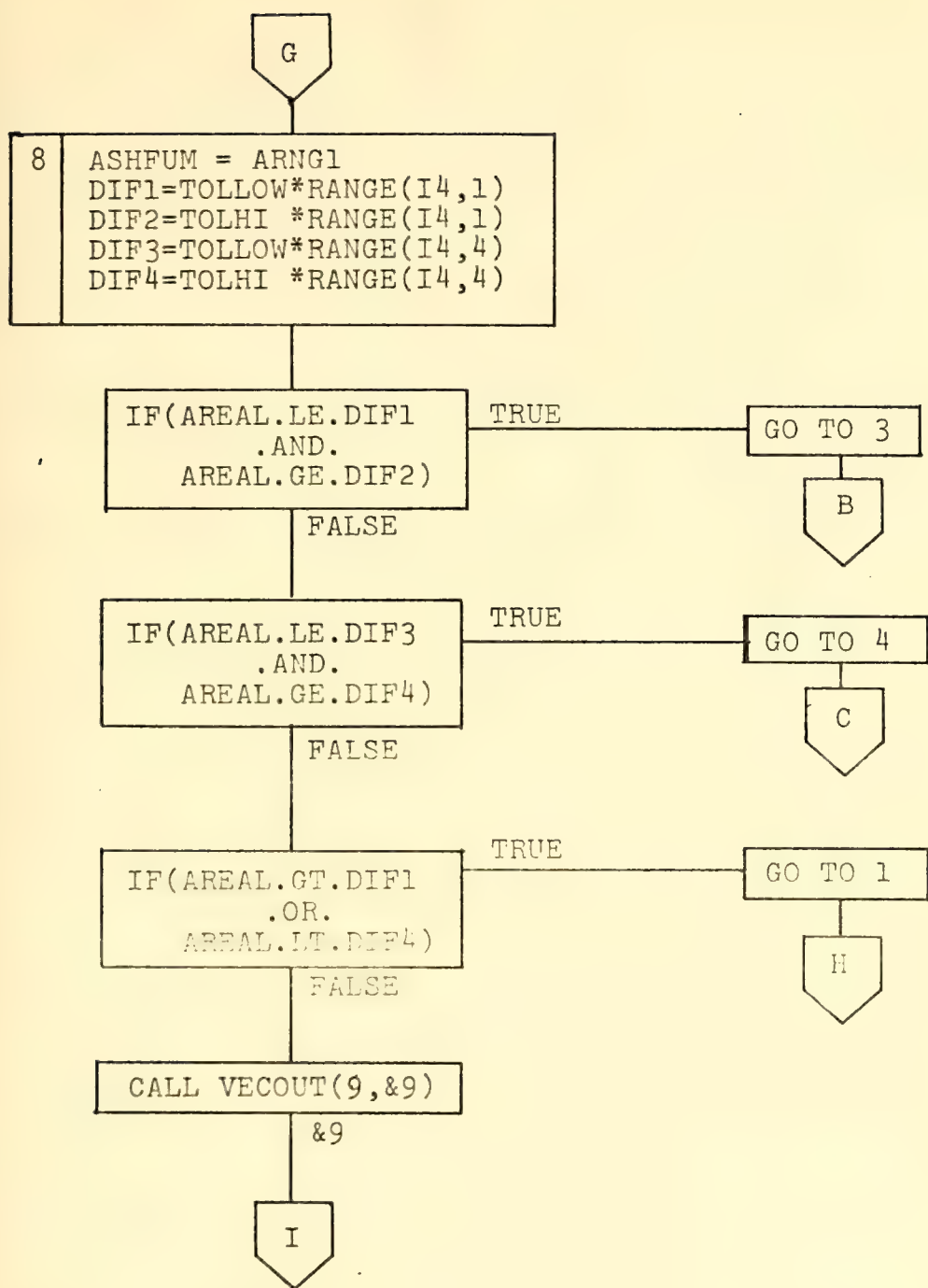


FIGURE 15 continued

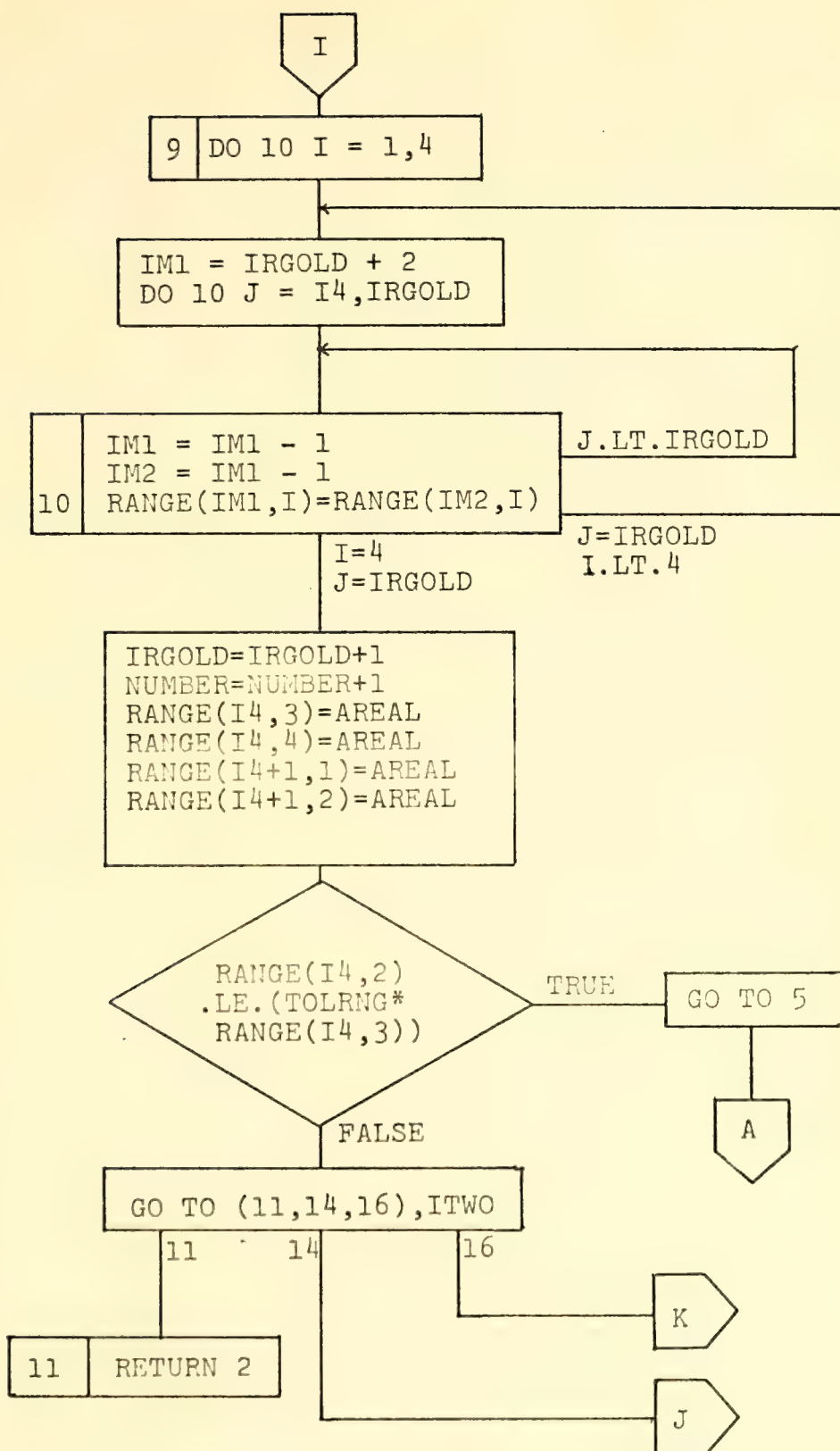


FIGURE 15 continued

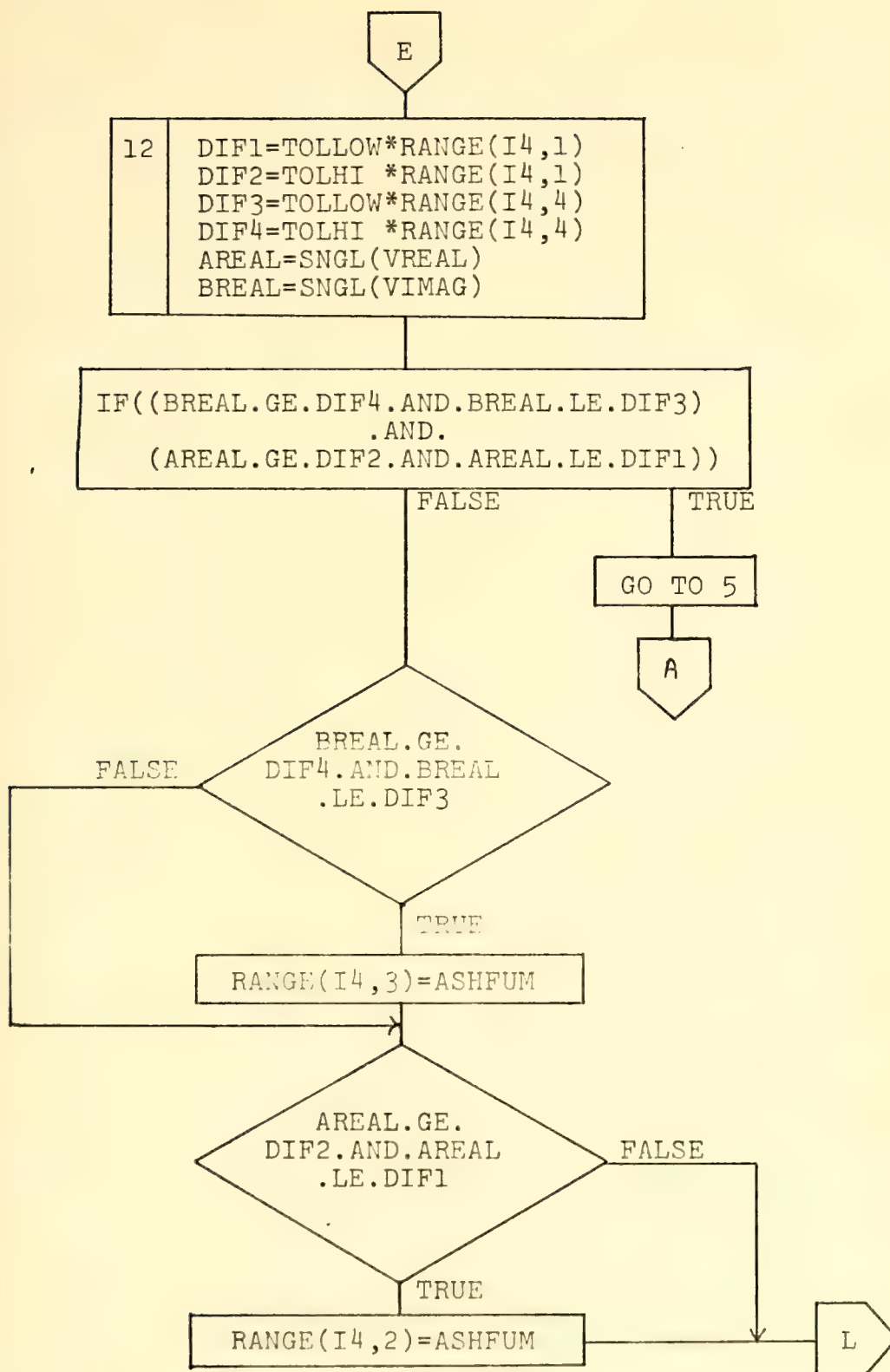


FIGURE 15 continued

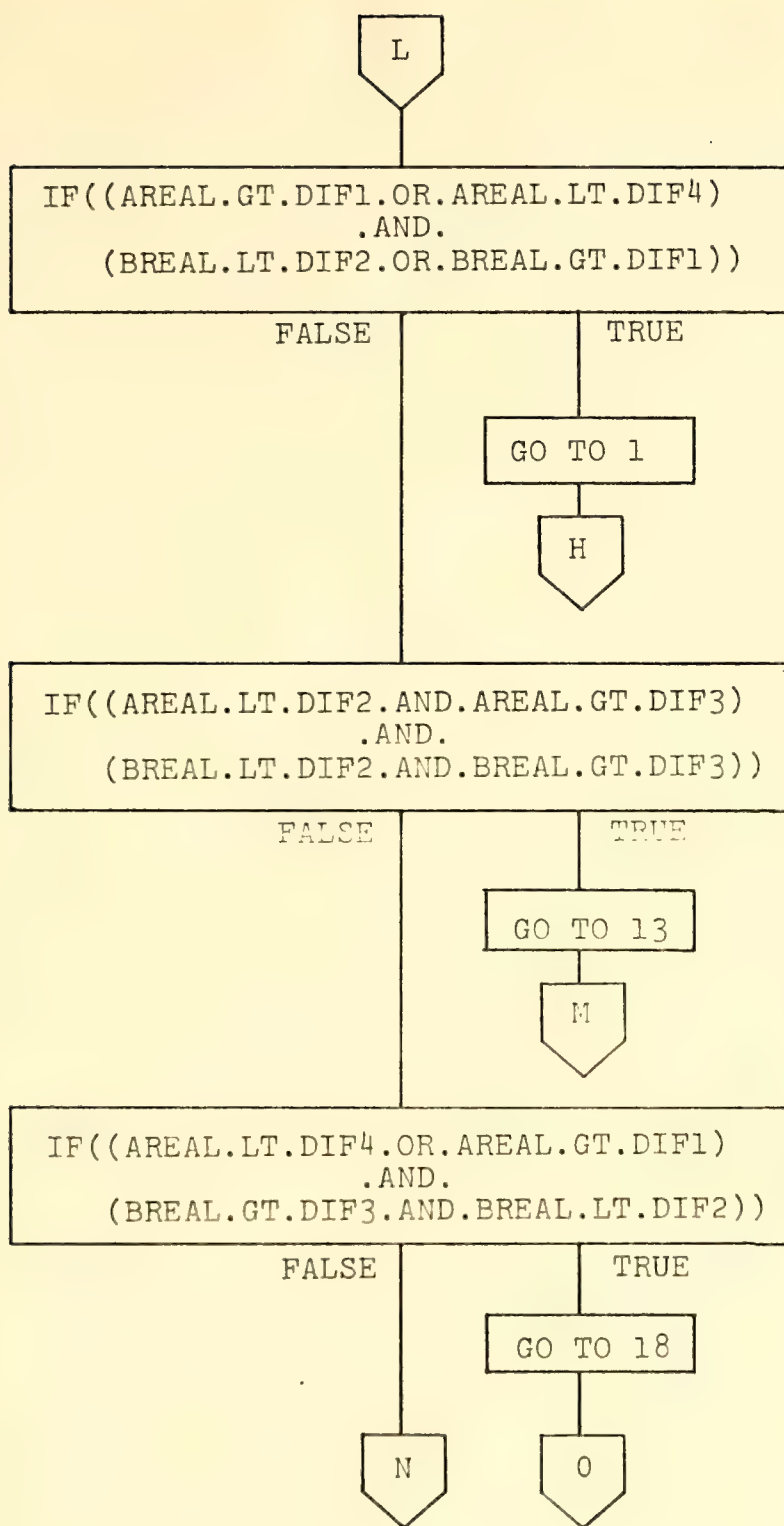


FIGURE 15 continued

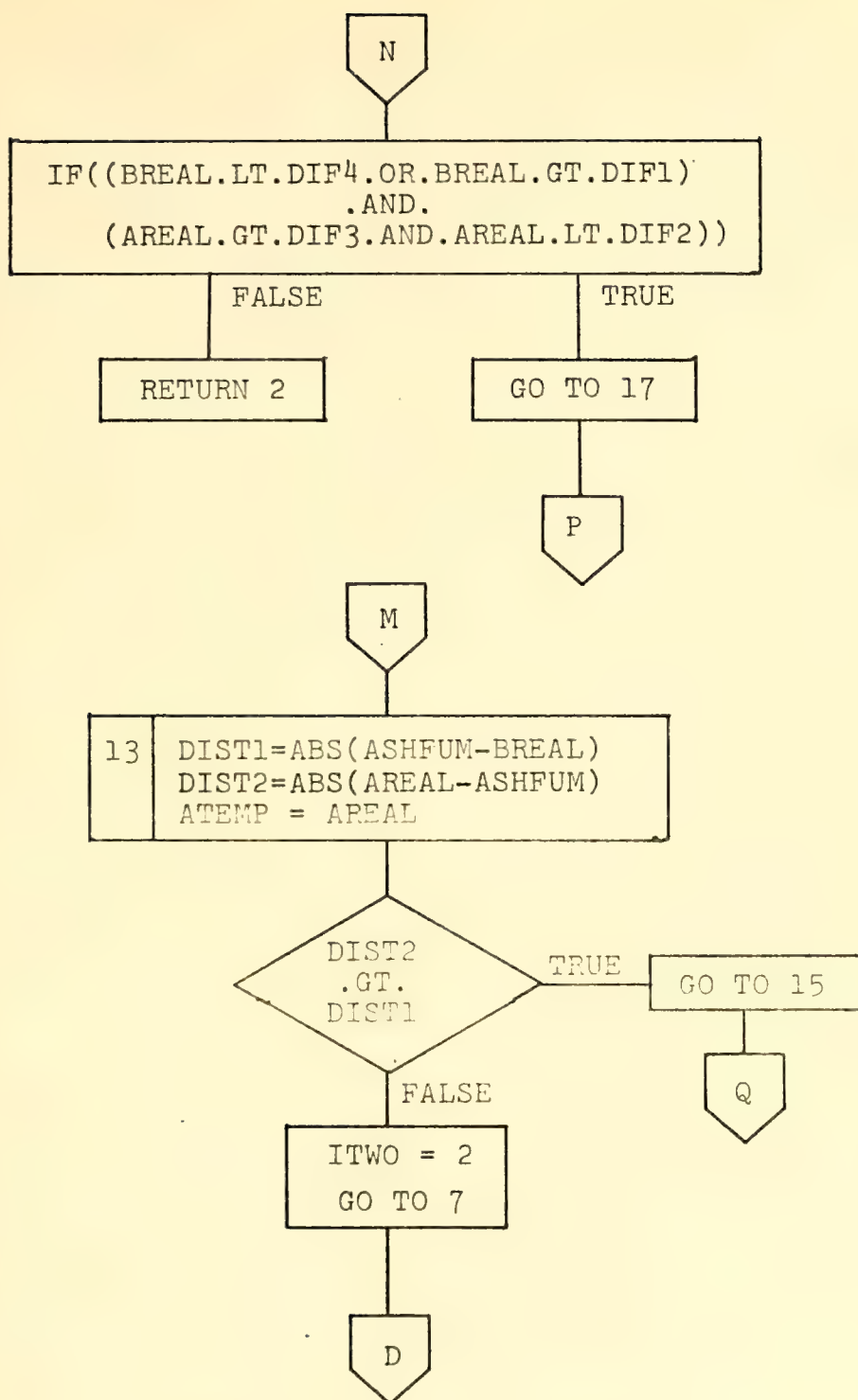


FIGURE 15 continued

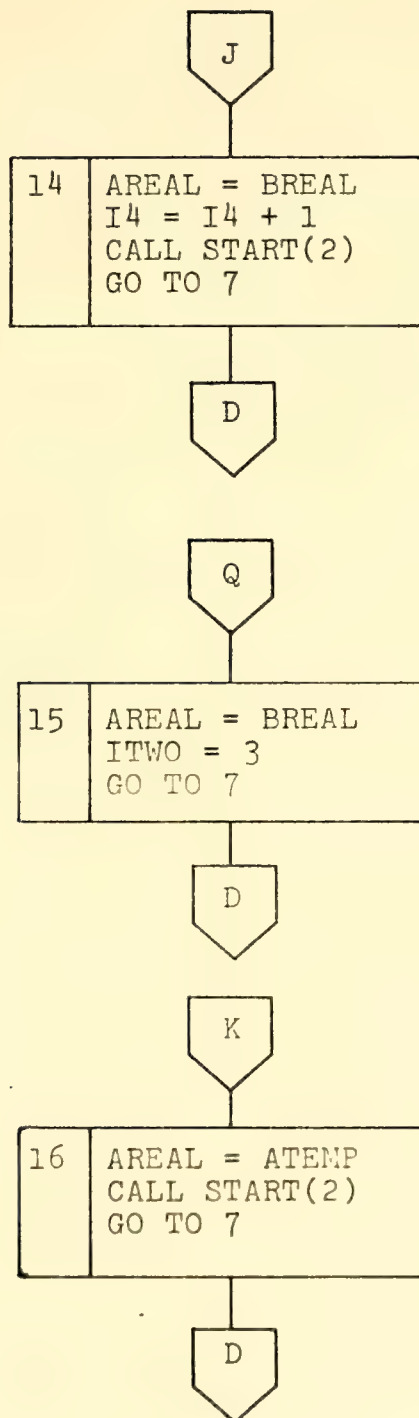


FIGURE 15 continued

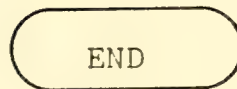
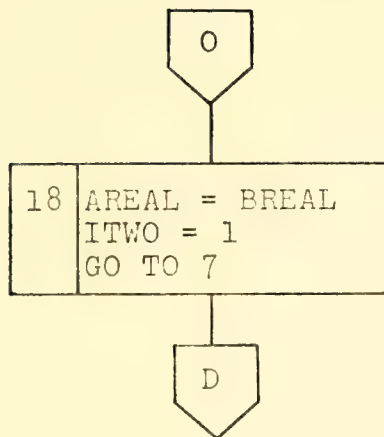
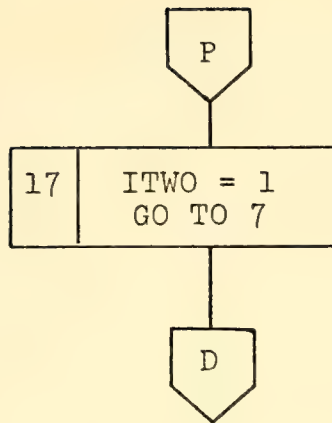


FIGURE 15 continued

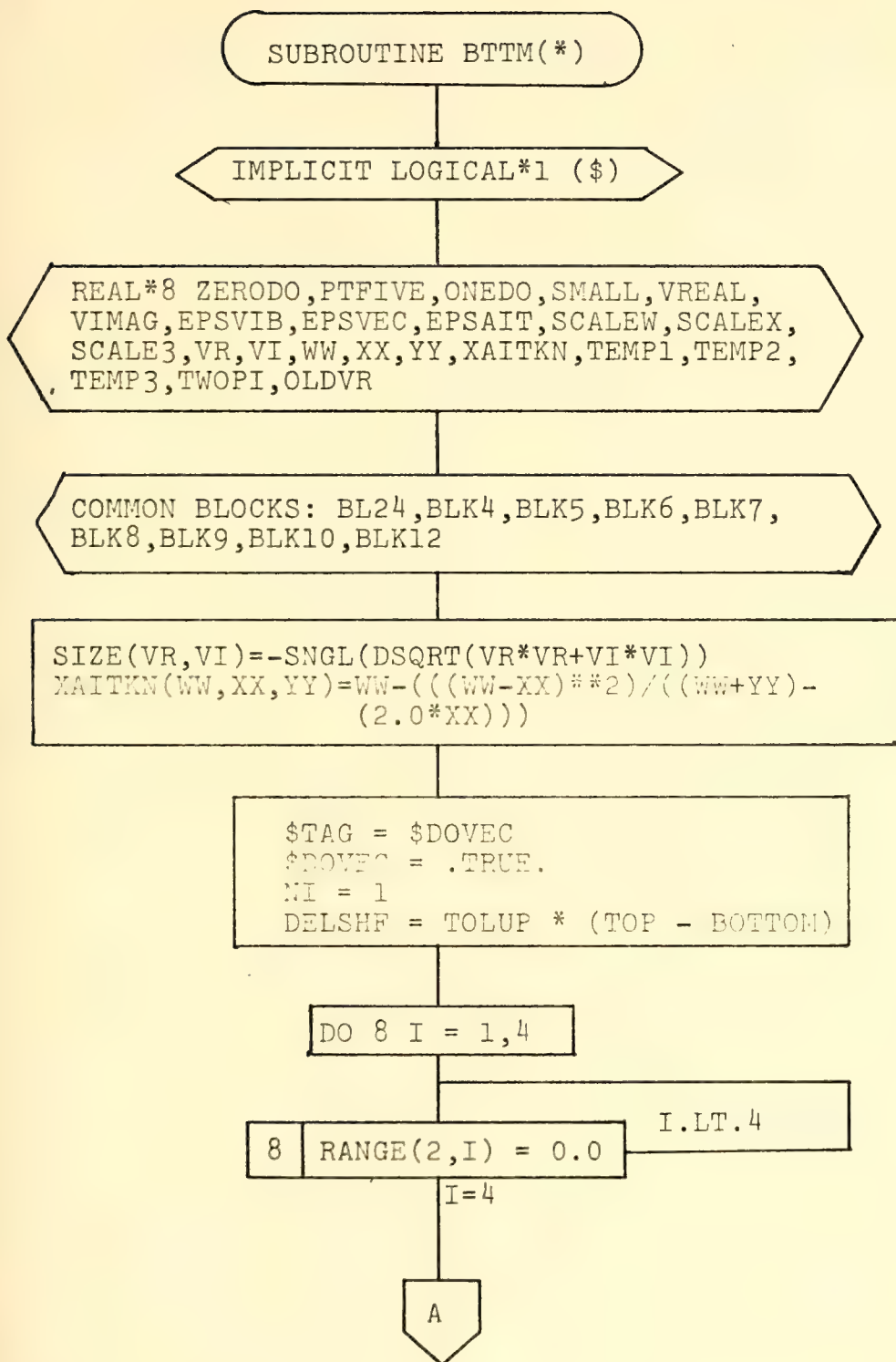


FIGURE 16 SUBROUTINE BTM(*) FLOWCHART

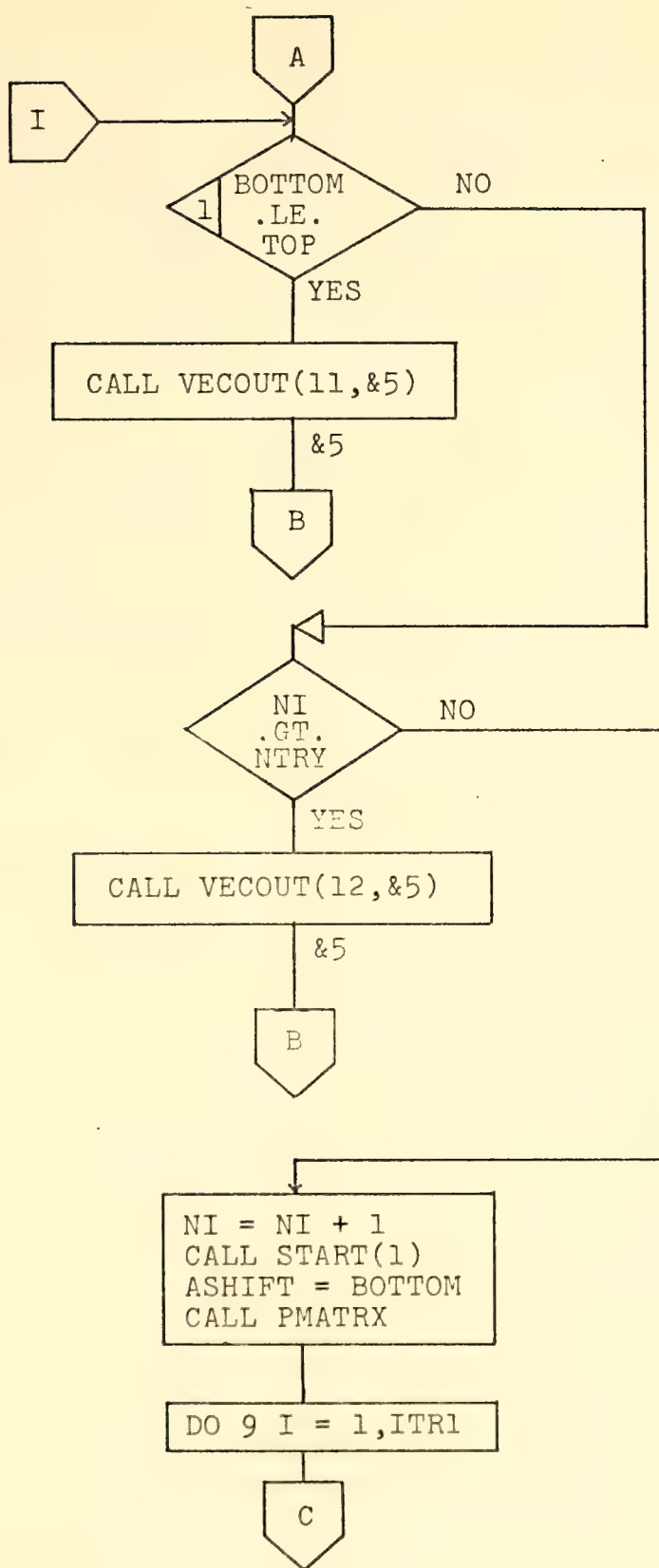


FIGURE 16 continued

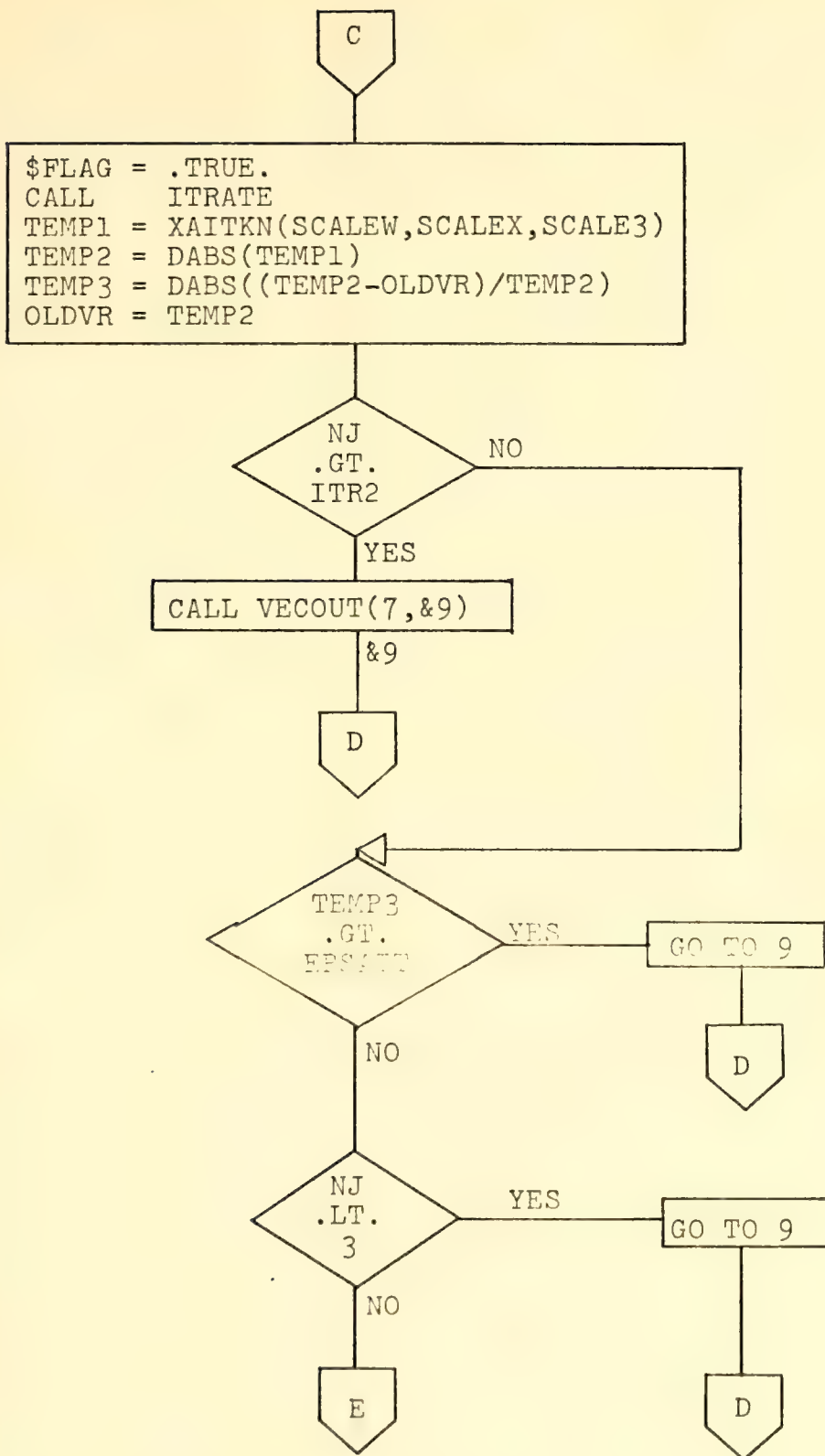


FIGURE 16 continued

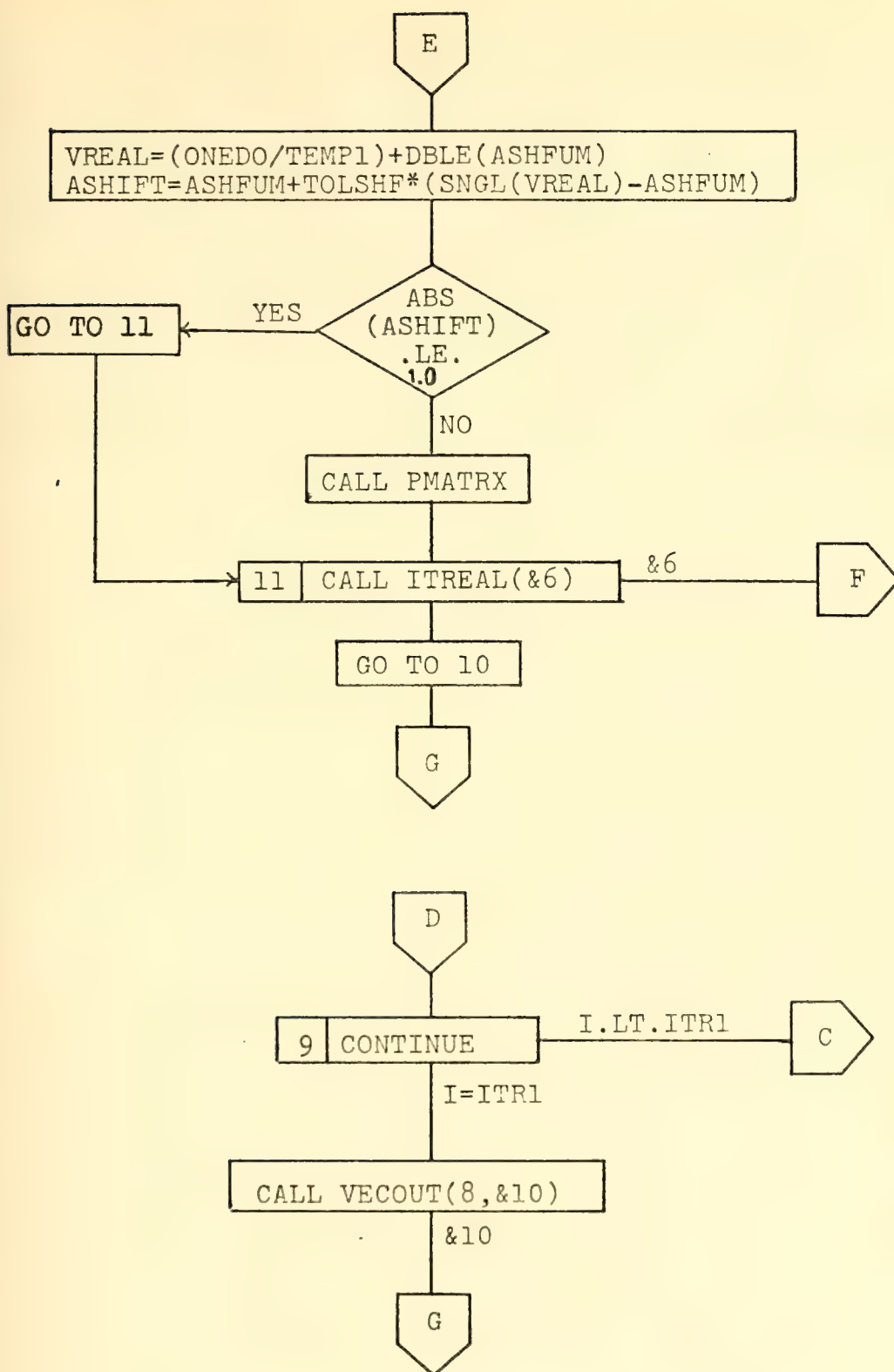


FIGURE 16 continued

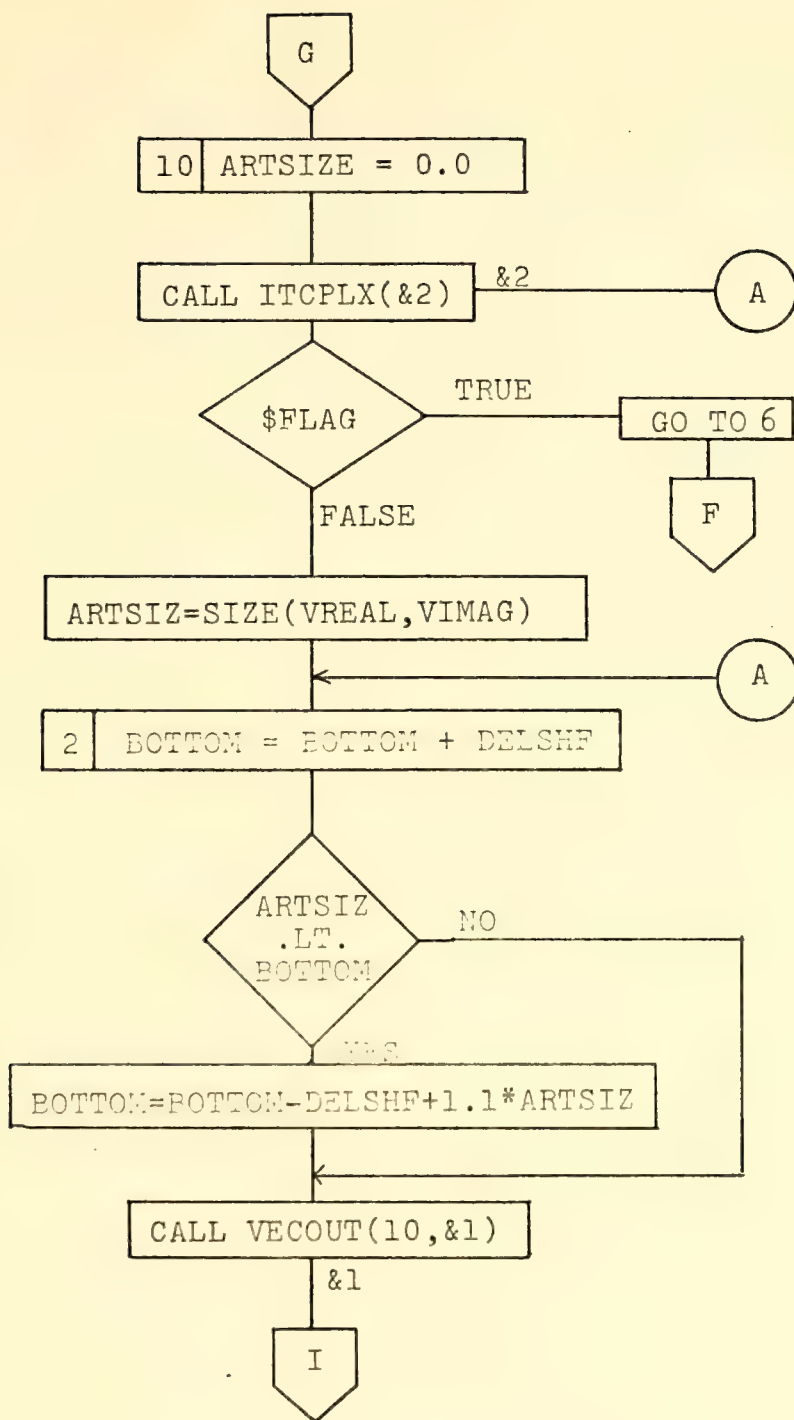


FIGURE 16 continued

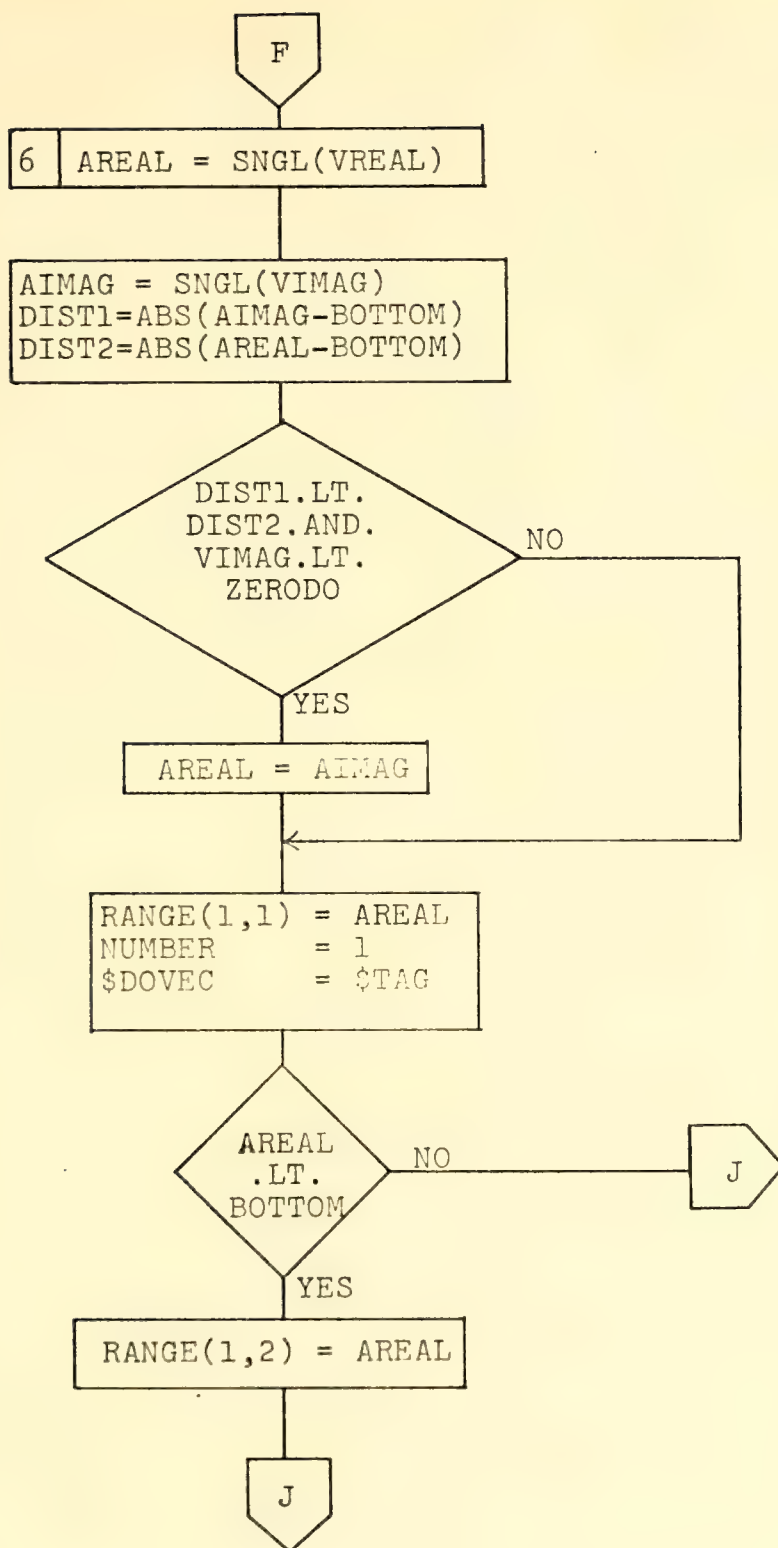


FIGURE 16 continued

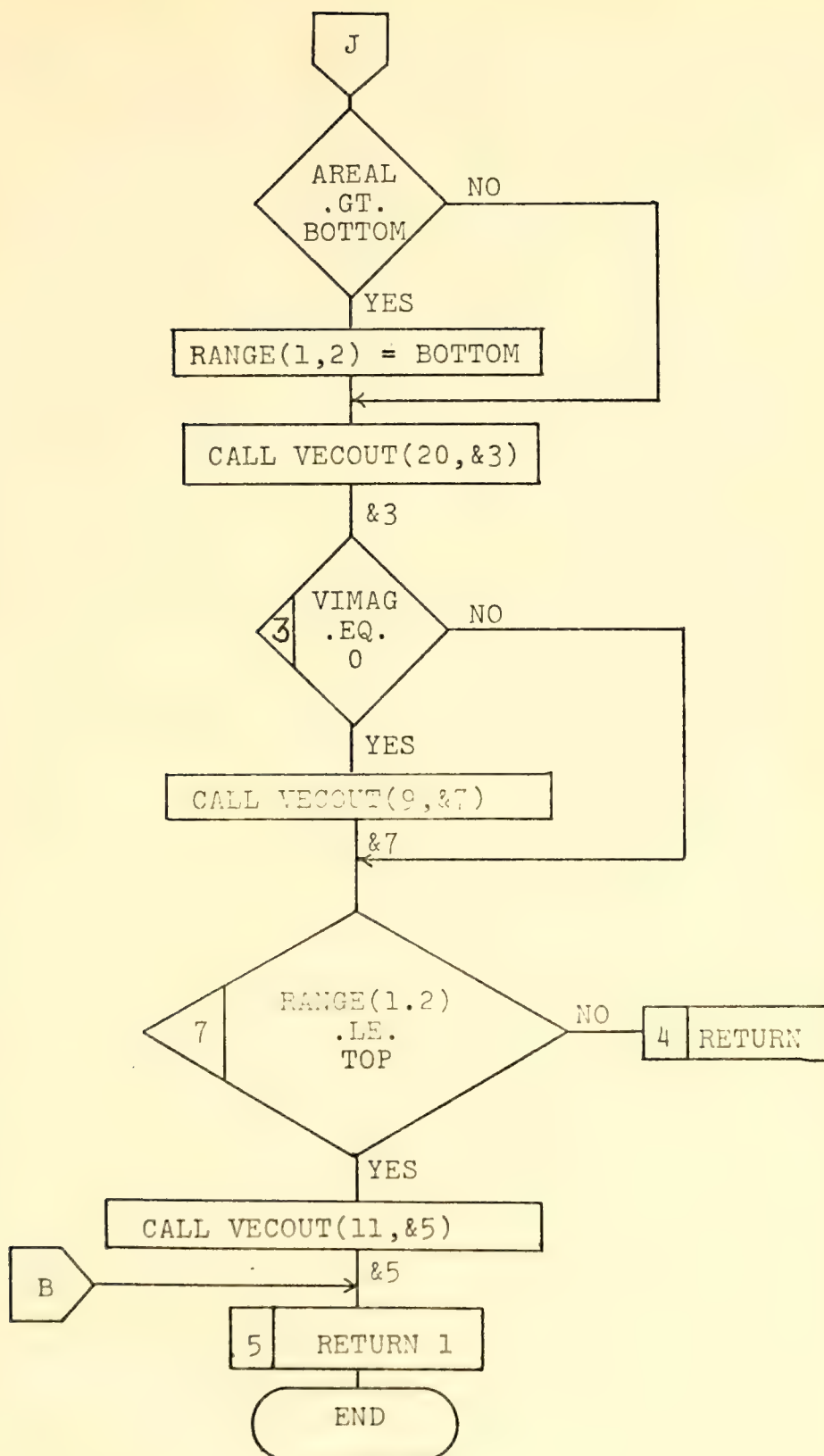


FIGURE 16 continued

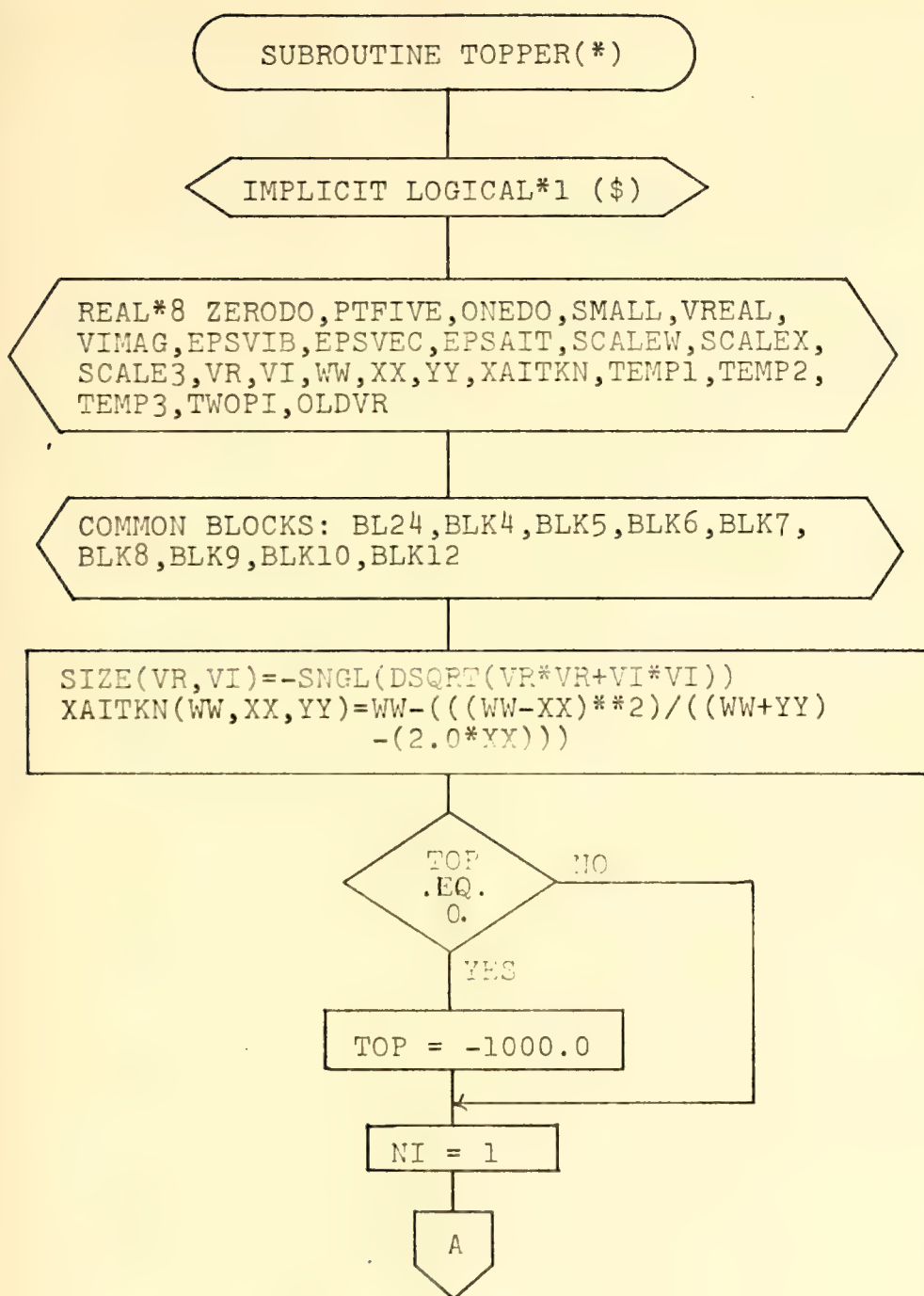


FIGURE 17. SUBROUTINE TOPPER(*) FLOWCHART

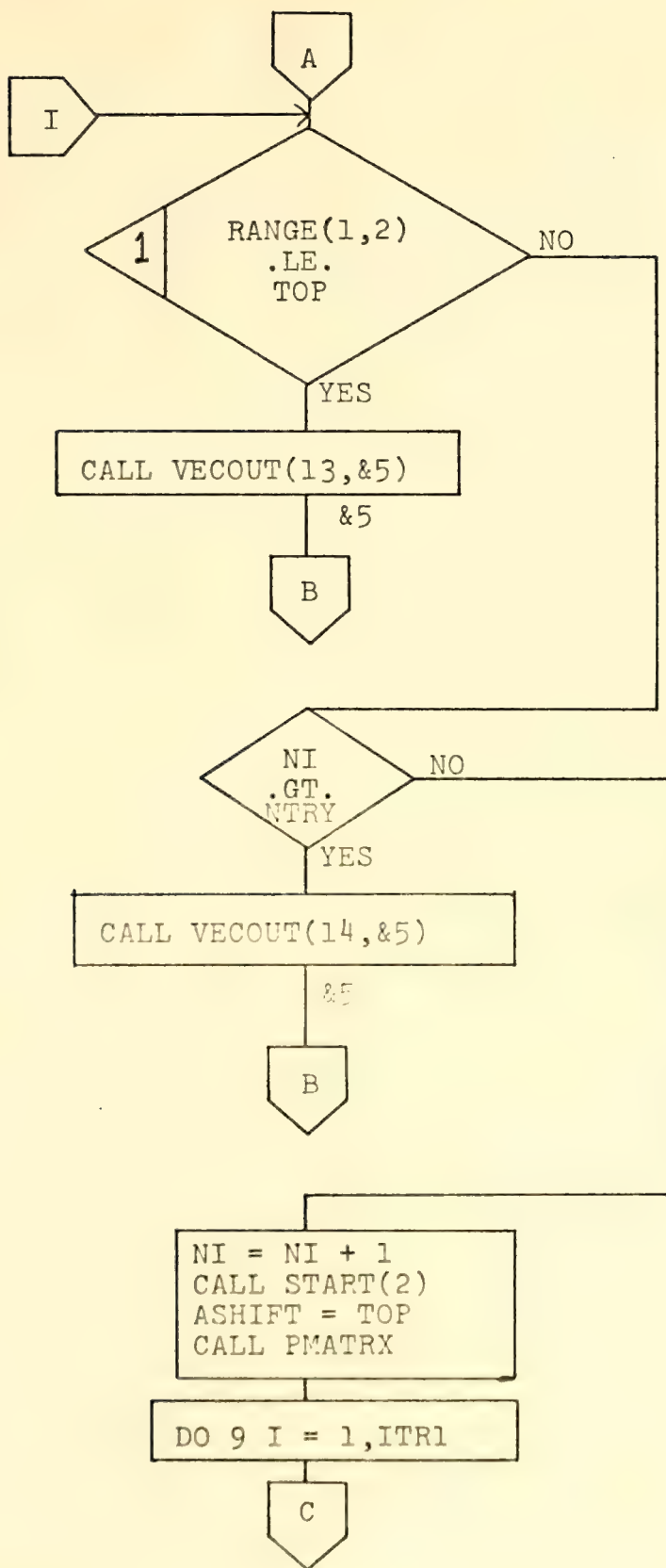


FIGURE 17 continued

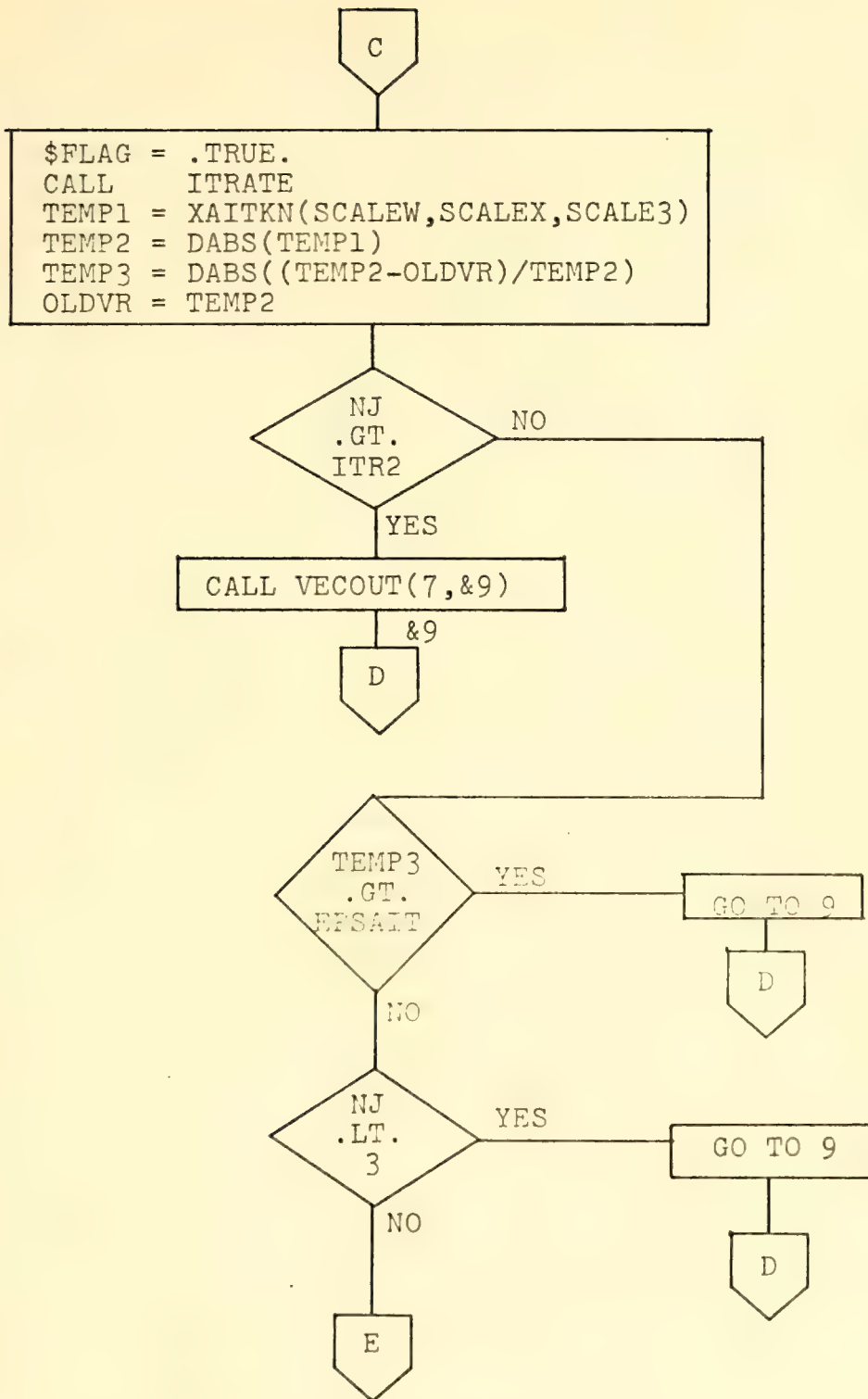


FIGURE 17 continued

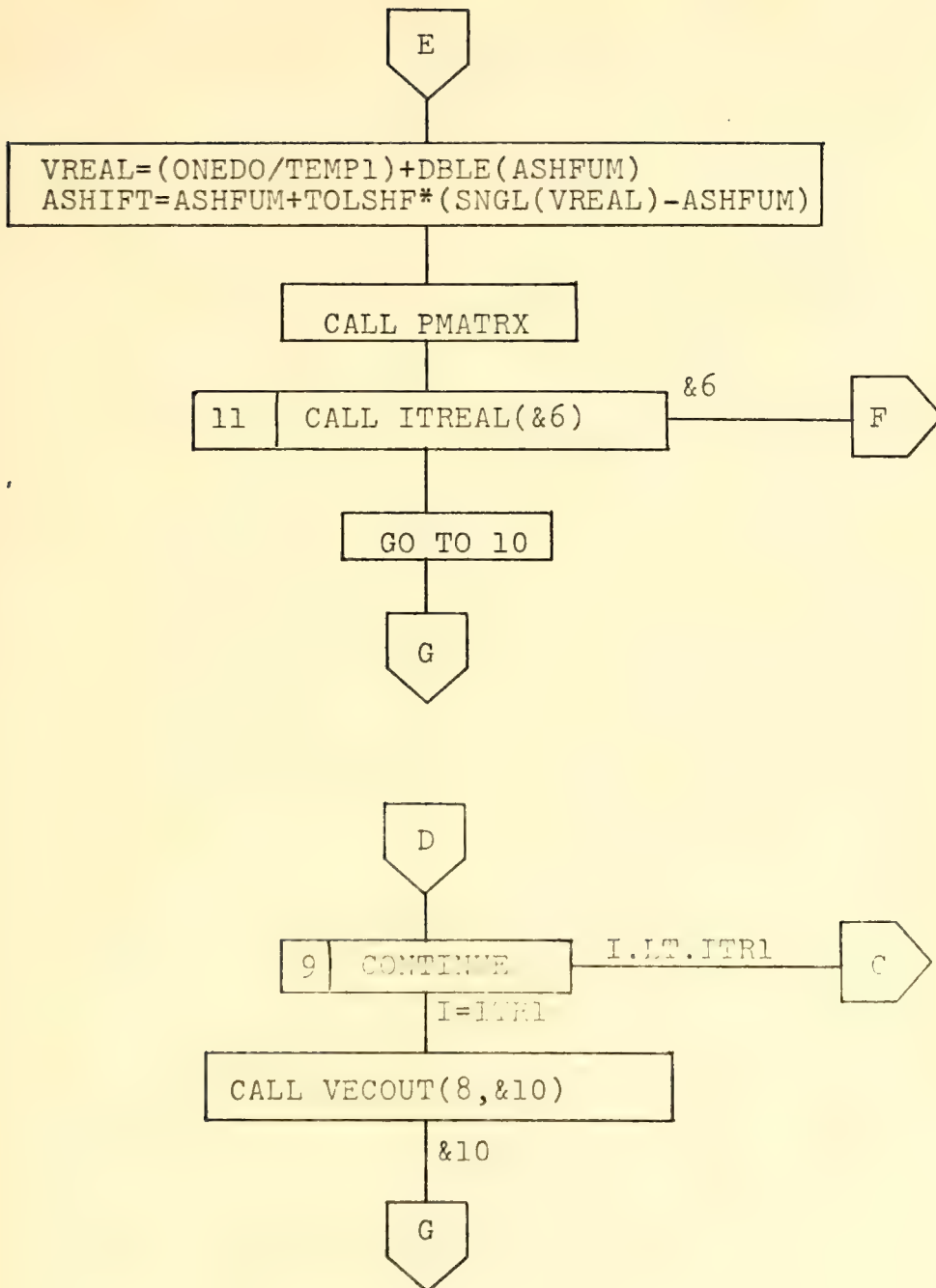


FIGURE 17 continued

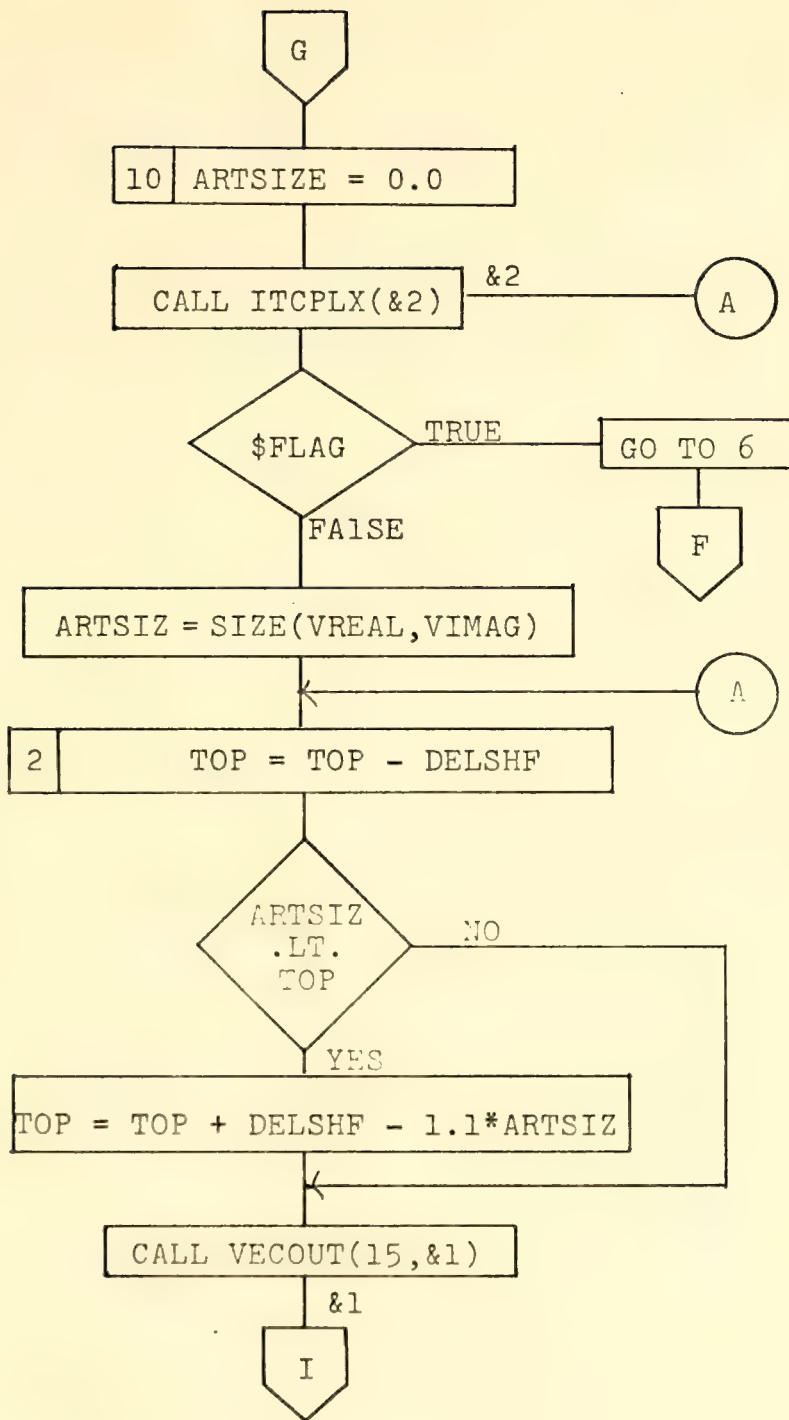


FIGURE 17 continued

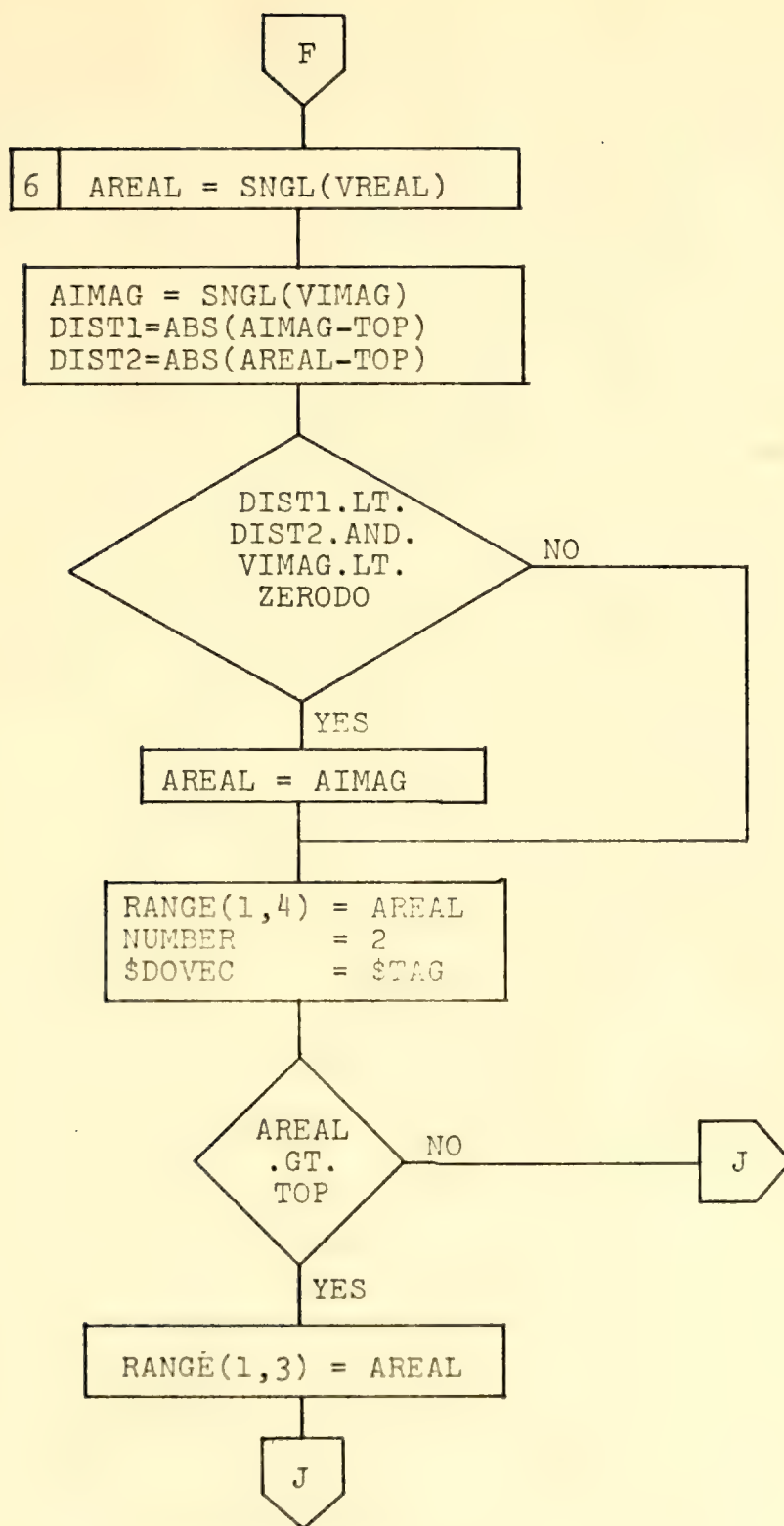


FIGURE 17 continued

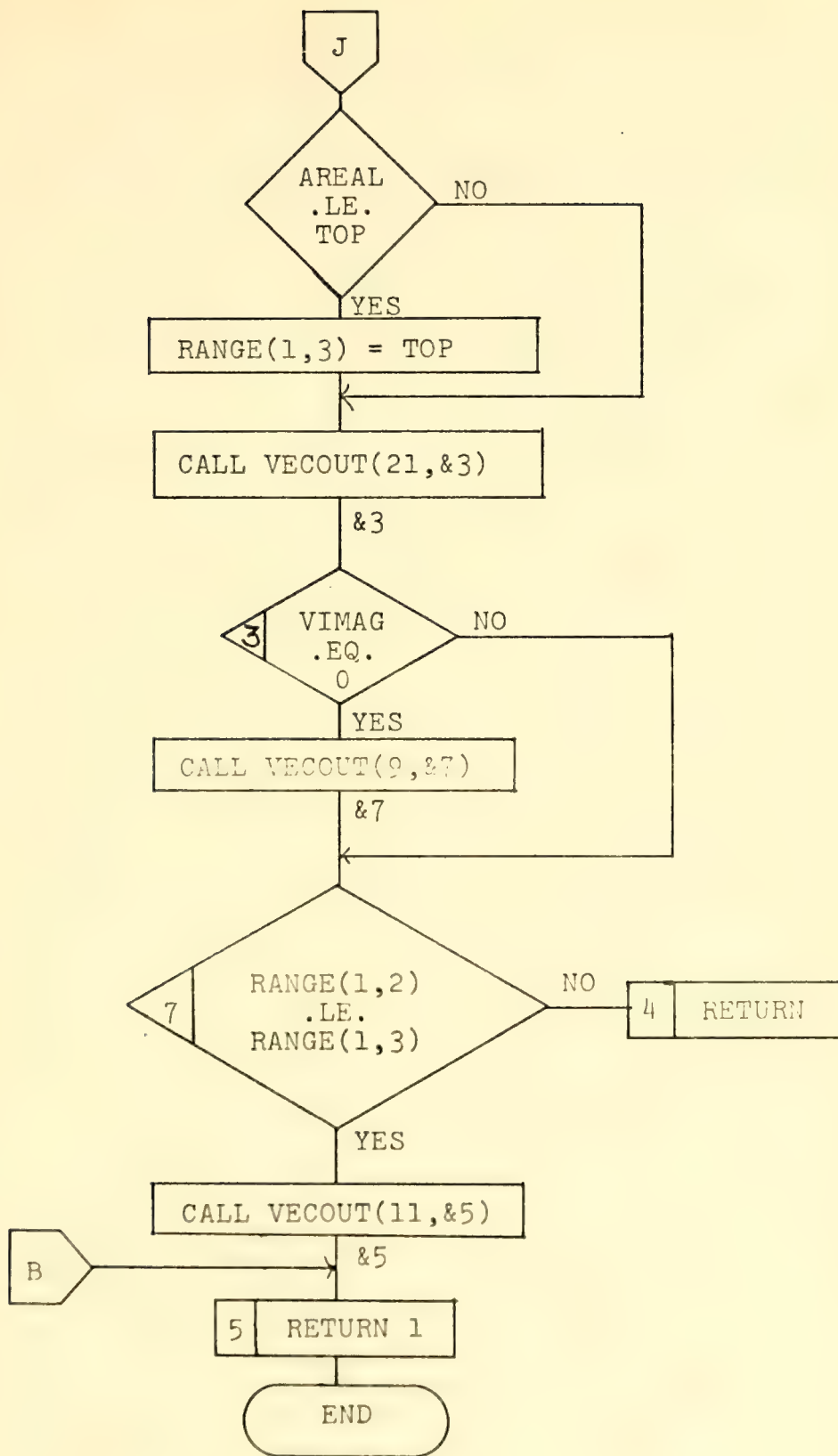


FIGURE 17 continued

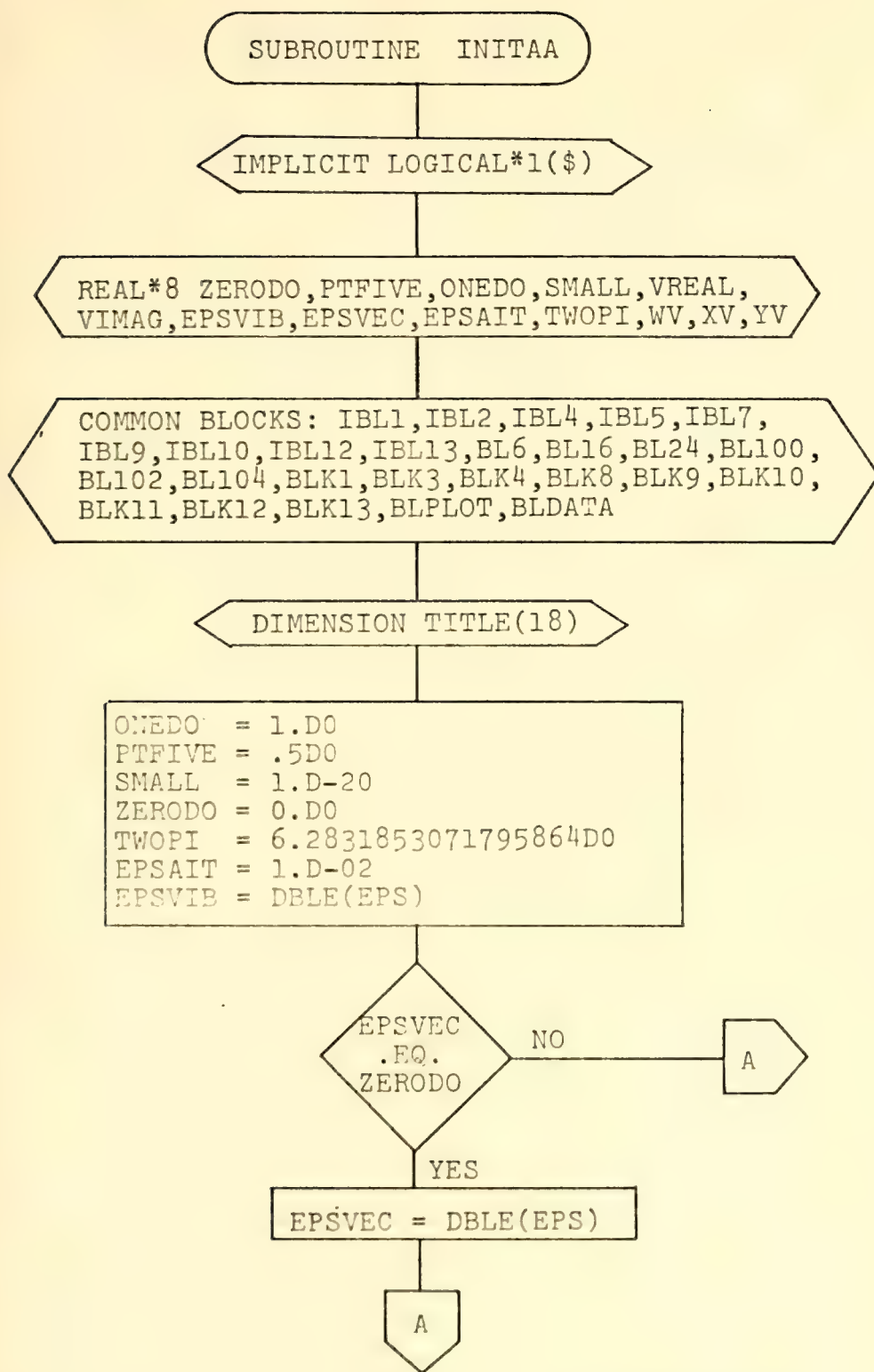


FIGURE 18. SUBROUTINE INITAA FLOWCHART

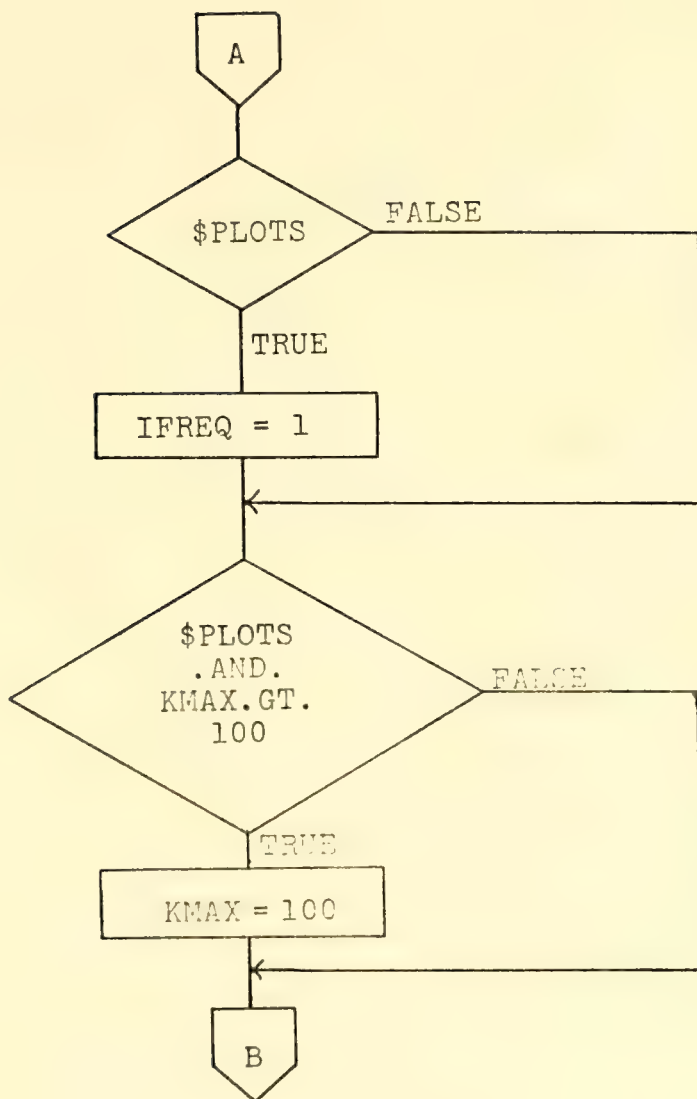


FIGURE 18 continued

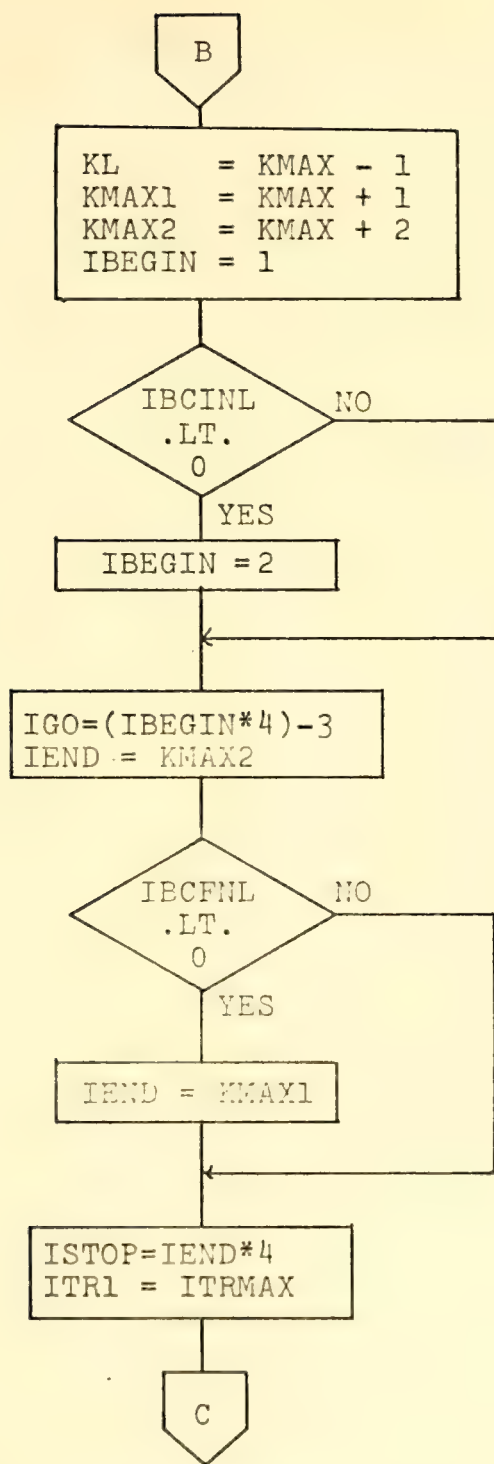


FIGURE 18 continued

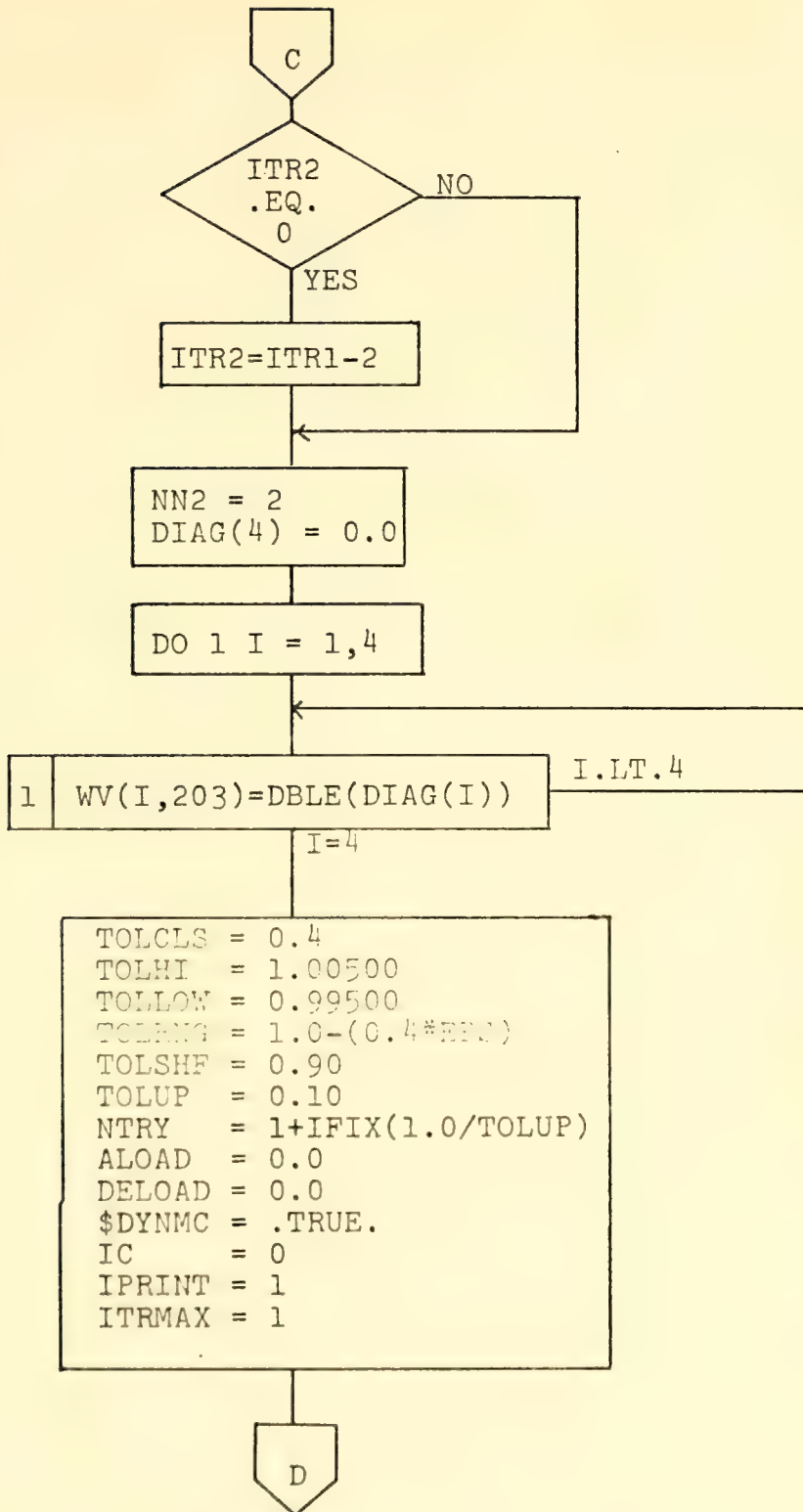


FIGURE 18 continued

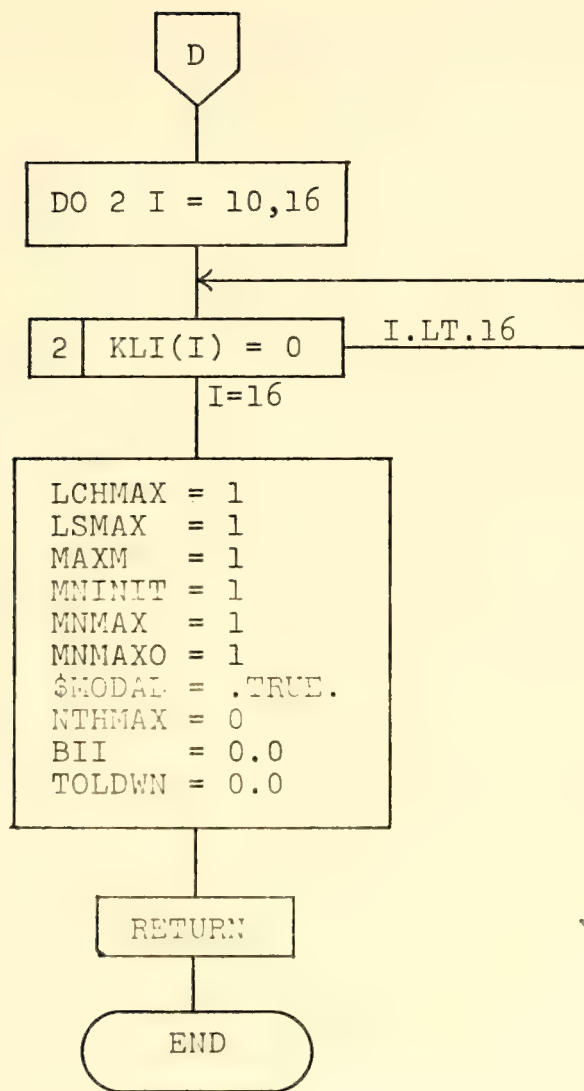


FIGURE 18 continued

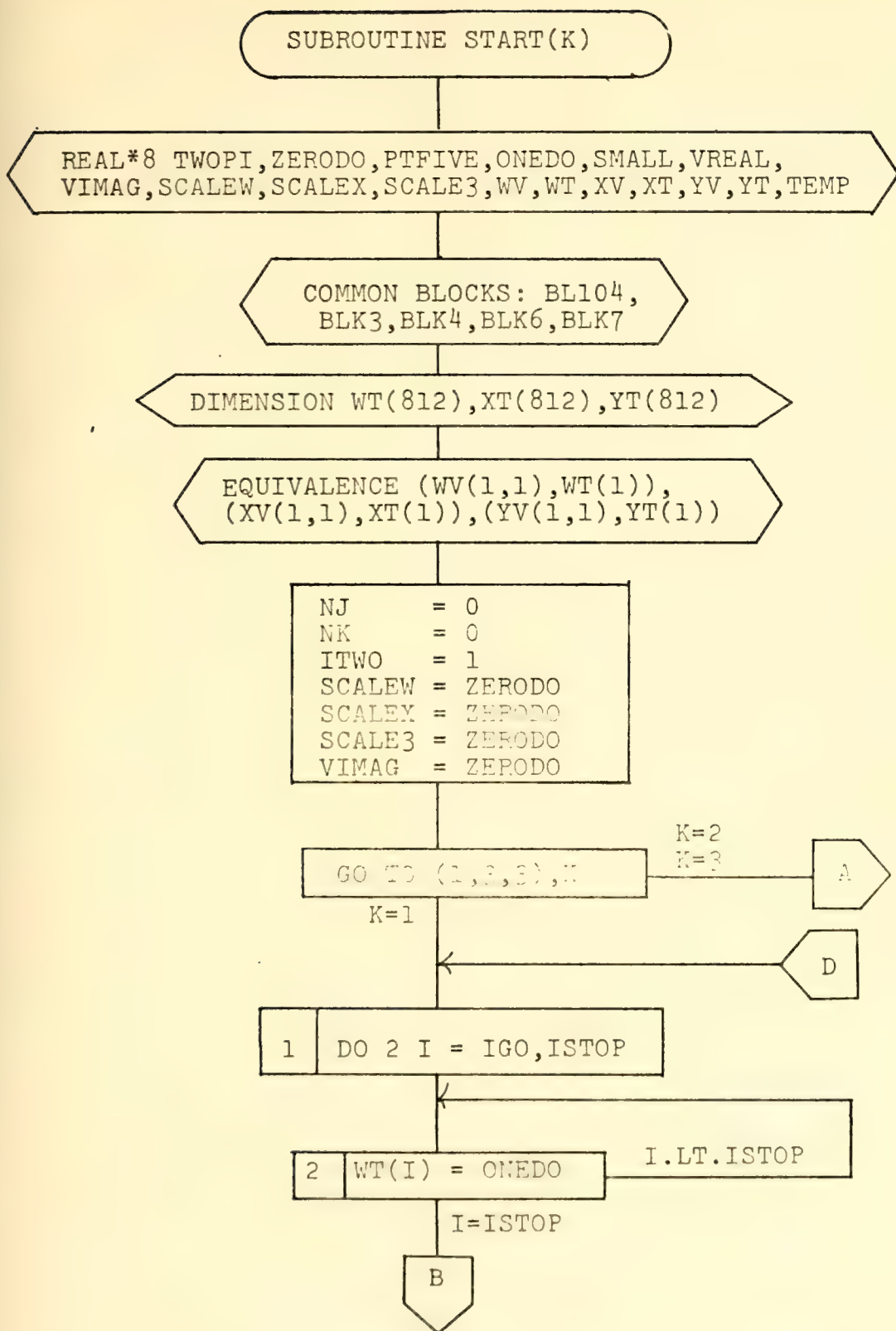


FIGURE 19. SUBROUTINE START(K) FLOWCHART

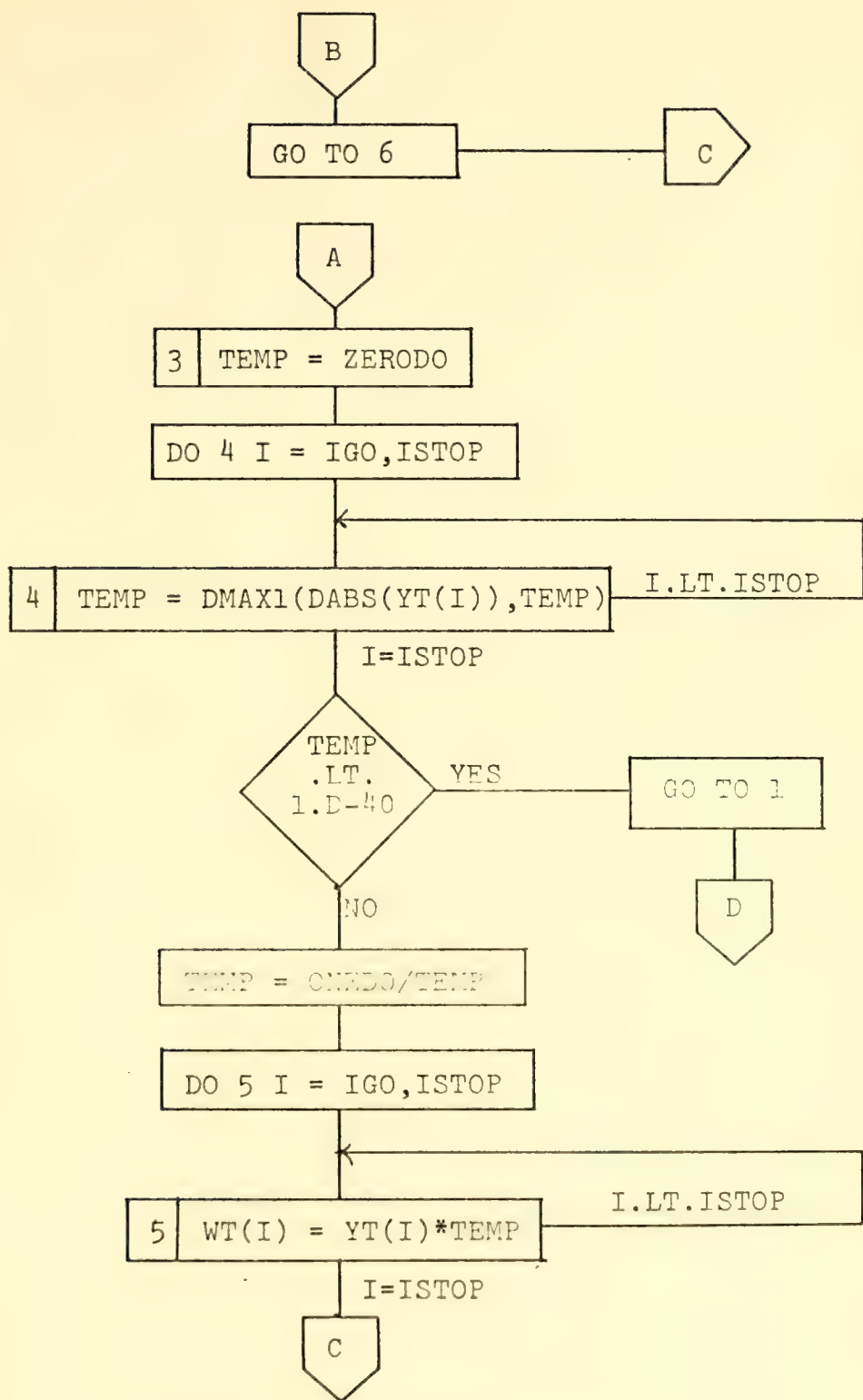


FIGURE 19 continued

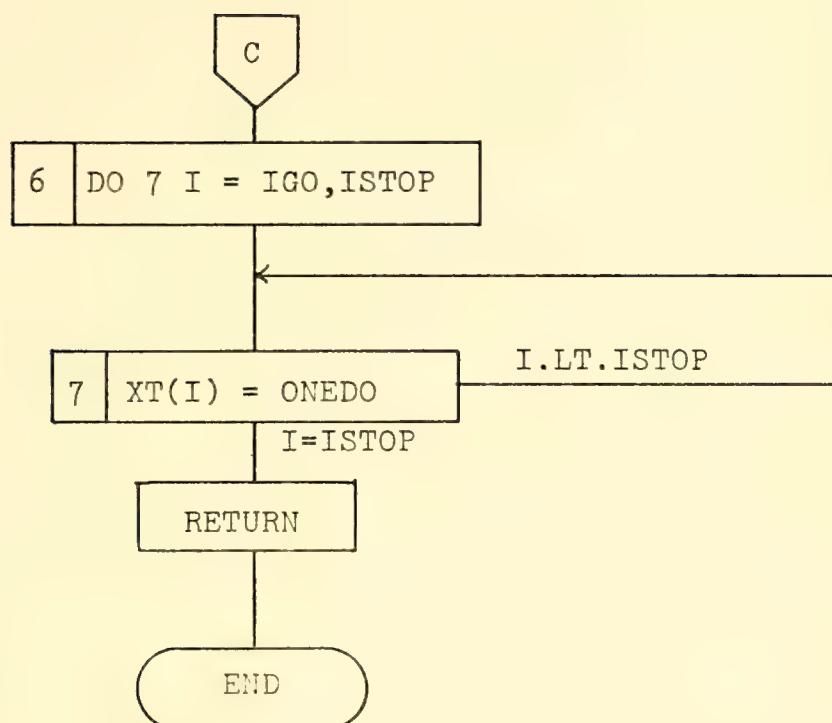


FIGURE 19 continued


```

THE LOWEST FREQUENCY IN HARMONIC 3 IS DETERMINED
DIAGONAL OF MASS MATRIX (MU-BAR) IS ( 1. 1. 1. 0. )
THE CONVERGENCE TEST ON THE VECTOR WILL BE PERFORMED
CONVERGENCE CRITERION IS 0.10D-01

      CONVERGED SOLUTION. ITERATIONS =    18
RAYLEIGH QUOTIENT FREQUENCY =    0.40103772723439D 03 HZ
      ( SOLUTION VECTOR PRINTED HERE )

      3 SHIFT POINT(S) FOR HARMONIC 5 IS(ARE) PROVIDED
DIAGONAL OF MASS MATRIX (MU-BAR) IS ( 0. 0. 1. 0. )
THE CONVERGENCE TEST ON THE VECTOR WILL NOT BE PERFORMED

      CONVERGED SOLUTION. ITERATIONS =    7
RAYLEIGH QUOTIENT FREQUENCY =    0.43982589633472D 02 HZ
      ( OTHER SOLUTIONS FOLLOW )

```

FIGURE 20. Subroutine VECOUT(IND,*) Print-out Samples


```

THIS IS A FREQUENCY RANGE SEARCH FOR HARMONIC 3

BOTTOM OF RANGE IS 0.7000E 01 HZ      TOP OF RANGE IS 0.1200E 02 HZ
BOTTOM = 0.4900E 02                  TOP = 0.8400E 02

    DIAGONAL OF MASS MATRIX (MU-BAR) IS ( 1. 1. 1. 0. )

        BOTTOM = 0.4900E 02
        LOWEST EIGENVALUE (RANGE(1,1)) = 0.5300E 02
        RANGE(1,2) = 0.5300E 02

        CONVERGED SOLUTION. ITERATIONS = 9

    RAYLEIGH QUOTIENT FREQUENCY = 0.8358963820957D 01 HZ

        ( SOLUTION VECTOR PRINTED HERE )

        TOP = 0.8400E 02
        HIGHEST EIGENVALUE (RANGE(1,4)) = 0.7000E 02
        RANGE(1,3) = 0.7000E 02

        CONVERGED SOLUTION. ITERATIONS = 11

    RAYLEIGH QUOTIENT FREQUENCY = 0.1000000000000E 02 HZ

        ( OTHER SOLUTIONS FOLLOW )

    5 FREQUENCIES HAVE BEEN FOUND

```

FIGURE 20. continued

Diagnostic Messages:

```

EPS IS VERY SMALL ( 0.10D-09 )

CHECK PERMISSIBLE NUMBER OF ITERATIONS ( 3 )

NO CONVERGENCE TO A REAL EIGENVALUE AFTER 99 ITERATIONS
RAYLEIGH QUOTIENT FREQUENCY = 0.12345678910111D 04 HZ
{THE FREQUENCY IS IMAGINARY}
THE LAST, NEXT TO LAST AND NEXT TO NEXT TO LAST EIGENVALUES ARE
-0.987654321098D 02 -0.987654321005D 02 -0.987656789876D 02

NO CONVERGENCE AFTER 99 ITERATIONS
EIGENVALUE(S) ARE 0.123456D 01 0.123456D-01
THE LAST, NEXT TO LAST AND NEXT TO NEXT TO LAST VECTOR ELEMENT MAXIMUMS ARE
0.123456789102D 03 -0.987654323456D-04 0.123456789345D 04

CONVERGED SOLUTION - TWO REAL EIGENVALUES
AN INCREASE IN THE CONVERGENCE CRITERIA (EPS) AND/OR AN INCREASE IN THE PERMISSIBLE NUMBER OF
ITERATIONS(ITRMAX) IS RECOMMENDED AS A POSSIBLE SOLUTION TO THE PROBLEM OF A POORLY CONDITIONED MATRIX.
ITERATIONS ARE 99
{THE FIRST FREQUENCY IS IMAGINARY}
{BOTH FREQUENCIES ARE IMAGINARY}

CONVERGED SOLUTION - COMPLEX EIGENVALUE
ITERATIONS ARE 99 EIGENVALUE IS 0.123456D 02 0.123456D-02

THE RANGE SIZE HAS BEEN REDUCED
BOTTOM OF RANGE IS NOW 0.123456E 01

UNABLE TO DETERMINE A MINIMUM FREQUENCY AFTER 10 TRIES

THE RANGE SIZE HAS BEEN REDUCED
TOP OF RANGE IS NOW 0.123456E 04

UNABLE TO DETERMINE A MAXIMUM FREQUENCY AFTER 10 TRIES
RANGE HAS BEEN COVERED

```

FIGURE 20. continued

APPENDIX D
SOME EXPERIENCE AND
RECOMMENDATIONS ON USING SATANS-III

Selecting the program mode which determines the minimum frequency for a given Fourier harmonic (circumferential wave number), KEY1 = 0, causes the vector test to be performed. To determine the minimum eigenvalue without performing the vector test, the supplied shift point program mode should be used, KEY1 = 1, with the shift point set to zero and KEY3 = 0.

The vector convergence test is intended for use only when there is some difficulty experienced in extracting a particular mode.

Three shift points per Fourier harmonic may be supplied by the user, KEY1 = 3, on one card. The starting vector for the first value is all ones. The starting vector for the one or two subsequent values is determined by the pseudo sweeping technique developed for subroutine RANGER. However, if one of those values is zero, the starting vector will be all ones. Three shift points enable a difficult mode to extract to be bracketed.

In the frequency range search operation the user supplies the upper and lower bounds of the range. In the lower modes the iteration process is sensitive to the choice of starting vectors. On infrequent occasions temporary convergence to one of two closely spaced eigenvalues

might cause a mode to be missed. This may be avoided by making the convergence criterion very tight, using the vector test and using a large number of iterations. This is a high price to pay for the average case and the supplied shift point mode of the program is a more economical approach and the recommended course of action. The simultaneous determination of the mode shapes provides an easy method of spotting if and which mode is missing.

Because the starting vectors are biased toward the lower frequencies the range bounds supplied by the user may not be the range actually searched by SATANS-III. The range actually searched is from BOTTOM to TOP as subsequently determined by subroutine RANGER. If, for example, a user specifies the range 1000 to 2000 Hz the bias toward lower frequencies might cause the actual search range to be from 800 to 1500 Hz. For this reason it is recommended that at least the upper bound be over-estimated to insure the complete search of the desired range. A good rule of thumb for the lower frequencies is an over-estimation of 50 to 100%. If a range is very small it might be searched more economically by the supplied shift method.

The only restriction on output is that only modal data is available. Since only one harmonic at a time is involved this was not thought to be a severe restriction. No matter what the input value is NTHMAX is subsequently set to zero.

In plotting output it must be remembered that KMAX must be less than 101.

Some difficulty has been encountered in nondimensionalizing and it is recommended that it not be employed. To avoid this difficulty set SIGO, ELAST, TKN and CHAR (input card three) to 1.0. Adjustments in the relative magnitude of the shift point values may be made using TEE0.

It was discovered that using the Naval Postgraduate School's IBM-360 under OS/MVT, Release 18, and the catalogued procedure FORTHCLG overflowed the linkage editor symbol table. This was corrected by the specification PARM.LINK='SIZE=(150K,20480),LIST,MAP',REGION.LINK=200K

APPENDIX E

SATANS-III INPUT CARD DATA GUIDE

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
1	1-72	18A4	TITLE	-	Enter any 72 characters

2	1- 5	I5	NO	1	The problem number, 0<NO<100000.
2	6- 8	L3	\$DYNMC	F T	\$DYNMC = F for a static analysis. \$DYNMC = T for dynamic or vibration analyses.
2	9-10	L2	\$VIBES	F T	\$VIBES = F for dynamic and static analyses. \$VIBES = T for a vibration analysis.
2	11-15	I5	IMODE	0 1	For no modal output data. For modal output data.
2	16-20	I5	NDIMEN	0 1	Dimensional output data. Nondimensional output data.
2	21-25	I5	NTHMAX	8	Summed solution will be printed at NTHMAX meridians, 0<=NTHMAX<=36. Not applicable in a vibration analysis.
2	26-30	I5	IFREQ	3	Solution will be printed at the first and last stations and every IFREQth intermediate station.
2	31-35	I5	IPRINT	2	Every IPRINTth converged solution will be printed. Not applicable in a vibration analysis.

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
2	36-40	I5	IBCINL	-1 0	If the shell has a pole at the first station. If the shell does not have a pole at the first station.
2	41-45	I5	IBCFNL	-1 0	If the shell has a pole at the last station. If the shell does not have a pole at the last station.
2	46-50	I5	KMAX	25	The number of meridional stations. KMAX<201 If plots are desired KMAX<101.
2	51-55	I5	MNMAX	7	The number of Fourier series coefficients used to describe the initial conditions, pressure and thermal loads. Not applicable in a vibration analysis.
2	56-60	I5	MAXM	8	The number of Fourier series coefficients used in describing the solution. MAXM>=MNMAX, MAXM<11 and MAXM * KMAX <201. Not applicable in a vibration analysis.
2	61-65	I5	LSMAX	1 99 750	For a linear analysis. Use many load steps for a nonlinear static analysis. For a dynamic analysis LSMAX is the number of time increments, where $LSMAX = T_{max} / \Delta T$. Not applicable in a vibration analysis.
2	66-70	I5	LCHMAX	3	The number of load step size reductions in a static analysis. Recommended range is 2-4.

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
				0	For a dynamic analysis. Not applicable in a vibration analysis
2	71-75	I5	ITRMAX	1 30	For a linear analysis. Maximum number of iterations at a load or time step or for a frequency. Up to 30 for a nonlinear analysis and 99 for a vibration analysis. Adjust as desired.
2	76-80	I5	IC	0 1	Initial conditions. Set to 0 for a static analysis, or for a dynamic analysis for a shell at rest at $T = 0$. For a dynamic analysis with initial conditions.

3	1-12	E12.3	NU	0.3	Poisson's ratio, ν .
3	13-24	E12.3	SIGO	1000.0 1.0	Reference stress level, σ_0 If the input data is dimensional.
3	25-36	E12.3	ELAST	.3E8 1.0	Reference modulus of elasticity, E_0 . If the input data is dimensional.
3	37-48	E12.3	TKN	.4E-2 1.0	Reference thickness, h_0 . If the input data is dimensional.
3	49-60	E12.3	CHAR	8.6 1.0	Characteristic shell dimension, a . If the input data is dimensional.

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
3	61-72	E12.3	TEEO	0.0 .966E-5 10.0	For a static analysis. Reference time, T_0 for a dynamic analysis. Nondimensionalizing time in a vibration analysis. Select in accordance with Eq (2).

4	1-12	E12.3	DELOAD	0.2 .8E-7	For a static analysis DELOAD is the load incre- ment. It remains un- changed until the solu- tion fails to converge in ITRMAX iterations. It is then reduced by a factor of five. A max- imum of LCHMAX reductions will occur before the program terminates. For a dynamic analysis DELOAD is the nondimen- sional time increment. LSMAX such time incre- ments are made. Not applicable in a vibration analysis.
4	13-24	E12.3	EPS	.01	Convergence criterion. Recommended range is .01 to .0001 for most applications. For a vibration analysis a somewhat tighter cri- terion may be desired.

Include as many cards 5 as necessary to specify the NTHMAX
meridians. If NTHMAX = 0 then card 5 is OMITTED.

5	1-72	6E12.3		10.0	A list of circumferential coordinates, θ , in degrees and tenths, at which the solution will be printed. There must be at least NTHMAX entries. Not applicable in a vibration analysis.
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Cards 6 through 23 describe the boundary conditions at the first and last stations. The boundary conditions exist on the total variables, not on the individual harmonics. If IBCINL = -1 (an initial pole) then OMIT cards 6 through 14, inclusive. If IBCFNL = -1 (a final pole) then OMIT cards 15 through 23, inclusive. Loadings specified through the edge boundary conditions are taken in the zeroth harmonic only. The column matrix { ℓ } is set to zero for all other harmonics. The boundary conditions are dimensional. The format of cards 6 through 23 is 4E16.8.

<u>Card 6,15</u>	<u>Card 7,16</u>	<u>Card 8,17</u>	<u>Card 9,18</u>	
$\Omega(1,1)$	$\Omega(1,2)$	$\Omega(1,3)$	$\Omega(1,4)$	$\left\{ \begin{array}{c} N_s \\ \hat{N}_s \\ \hat{Q}_s \\ \phi_s \end{array} \right\} +$
$\Omega(2,1)$	$\Omega(2,2)$	$\Omega(2,3)$	$\Omega(2,4)$	
$\Omega(3,1)$	$\Omega(3,2)$	$\Omega(3,3)$	$\Omega(3,4)$	
$\Omega(4,1)$	$\Omega(4,2)$	$\Omega(4,3)$	$\Omega(4,4)$	
<u>Card 10,19</u>	<u>Card 11,20</u>	<u>Card 12,21</u>	<u>Card 13,22</u>	<u>Card 14,23</u>
$\Lambda(1,1)$	$\Lambda(1,2)$	$\Lambda(1,3)$	$\Lambda(1,4)$	$\left\{ \begin{array}{c} U \\ V \\ W \\ M_s \end{array} \right\} = \left\{ \begin{array}{c} \ell(1) \\ \ell(2) \\ \ell(3) \\ \ell(4) \end{array} \right\}$
$\Lambda(2,1)$	$\Lambda(2,2)$	$\Lambda(2,3)$	$\Lambda(2,4)$	
$\Lambda(3,1)$	$\Lambda(3,2)$	$\Lambda(3,3)$	$\Lambda(3,4)$	
$\Lambda(4,1)$	$\Lambda(4,2)$	$\Lambda(4,3)$	$\Lambda(4,4)$	

<u>Card</u>	<u>Column</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
24	1- 2	L2	\$PLOTS	F	Indicates plots are NOT desired.
				T	Indicates plots are desired. KMAX<101
24	3- 4	L2	\$MODAL	F	Indicates plots are for summed solutions only
				T	Indicates plots are for modal solutions only.

For the remainder of card 24 entries, 0 indicates that no plots are desired for the particular item, and 1 indicates that they are desired. All graphs are plotted as the indicated item versus the station number. If a complete plot is desired, insure that IFREQ = 1.

24	5- 6	I2	IRADII	1	Plot the radii as computed by subroutine GEOM.
24	7- 8	I2	IGAMMA	1	Plot ρ'/ρ as computed by subroutine GEOM.
24	9-10	I2	IOMEGS	1	Plot ω_s as computed by subroutine GEOM.
24	11-12	I2	IOMEGT	1	Plot ω_θ as computed by subroutine GEOM.
24	13-14	I2	IDEOMS	1	Plot ω' as computed by subroutine GEOM.
24	15-16	I2	IBSTIF	1	Plot the stiffness d as computed by subroutine BDB.
24	17-18	I2	IDSTIF	1	Plot the stiffness d as computed by the subroutine BDB.
24	19-20	I2	IBBSTF	1	Plot the stiffness $db/d\zeta$ as computed by subroutine BDB.
24	21-22	I2	IDDSTF	1	Plot the stiffness $dd/d\zeta$ as computed by subroutine BDB.
24	23-24	I2	IPR	1	Plot the normal component of the pressure load.

<u>Card</u>	<u>Column</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
24	25-26	I2	IPS	1	Plot the meridional component of the pressure load.
24	27-28	I2	IPT	1	Plot the circumferential component of the pressure load.
24	29-30	I2	ITT	1	Plot the thermal load.
24	31-32	I2	IMT	1	Plot the thermal moment.
24	33-34	I2	IDTT	1	Plot $d/d\xi$ of the thermal load.
24	35-36	I2	IDMT	1	Plot $d/d\xi$ of the thermal moment.
24	37-38	I2	INS	1	Plot the meridional membrane force distribution.
24	39-40	I2	INTH	1	Plot the circumferential membrane force distribution
24	41-42	I2	INSTH	1	Plot the meridio-circumferential membrane force distribution.
24	43-44	I2	IQS	1	Plot the transverse force distribution.
24	45-46	I2	IMS	1	Plot the meridional moment distribution.
24	47-48	I2	IMTH	1	Plot the circumferential moment distribution.
24	49-50	I2	IMSTH	1	Plot the meridio-circumferential moment distribution.
24	51-52	I2	IU	1	Plot the meridional displacement distribution.
24	53-54	I2	IV	1	Plot the circumferential displacement distribution.

<u>Card</u>	<u>Column</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
24	55-56	I2	IW	1	Plot the normal displacement distribution.
24	57-58	I2	IPHIS	1	Plot the meridional rotation distribution.
24	59-60	I2	IPHIT	1	Plot the circumferential rotation distribution.
24	61-62	I2	IPHI	1	Plot the meridio-circumferential rotation distribution.

Cards 24A and 24B are only included in a SATANS-III vibration analysis and then only when \$VIBES is TRUE. If \$VIBES is FALSE (no vibration analysis to be performed) then cards 24A and 24B are OMITTED.

24A	1- 5	I5	IVIBES	4	The number of vibration analyses = the number of cards 24B to be included.
24A	6- 9	4F1.0	DIAG	1110	The elements of the diagonal of the mass matrix μ -bar. The 4th element is subsequently automatically set to 0.
24A	10-25	F16.8	EPSVEC	1.E-4	Vector test convergence criterion. If EPSVEC is left = 0.0 it is subsequently automatically set to EPS (card 4).
24A	26-30	I5	ITR2	50	ITR2 is a trouble-shooting aid. If ITR2 is entered every ITR2 iteration the Rayleigh quotient eigenvalue will be printed. If ITR2 is left = 0 it is subsequently automatically set to print the next to last solution in the event of non-convergence.

<u>Card</u>	<u>Column</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
-------------	---------------	---------------	-------------	----------------	----------------

Include one card 24B for each vibration analysis desired.

The analyses are done one harmonic at a time and all input information is stated on one card per harmonic. The total number of cards 24B = IVIBES. The information is stored in two arrays of three elements each, MODVIB(J,K) and SHFTPT(J,K) where J=1(1)3 for the Kth analysis and K=1(1)IVIBES.

24B	1- 5	I5	KEY1	0	The lowest frequency in the circumferential Fourier harmonic mode specified by KEY2 will be determined. The vector convergence test will automatically be performed.
				1,2, or 3	1,2 or 3 shift points are supplied by the user. Vector convergence test not performed unless so specified.
				4	A frequency range search will be performed for the mode specified by KEY2.
24B	6-10	I5	KEY2	8	The Fourier harmonic in the circumferential direction for which the vibration analysis will be performed.
24B	11-15	I5	KEY3	0	The vector convergence test will not be performed if KEY1=1,2,3 or 4.
				1	The vector convergence test will be performed.
24B	16-30	F15.8		1.E2	If KEY1=1,2 or 3 this is the first shift point. If KEY1=4 this is the lower bound of the frequency range to be searched. Units are Hz (CPS).

<u>Card</u>	<u>Column</u>	<u>Format</u>	<u>Item</u>	<u>Example</u>	<u>Meaning</u>
24B	31-45	F15.8		2.E4	If KEY1=2 or 3 this is the second shift point. If KEY1=4 this is the upper bound of the frequency range search. Units are Hz (CPS).
24B	46-60	F15.8		4.E3	Applicable only if KEY1=3 in which case this is the third shift point. Units are Hz(CPS).

25	1- 2	I2	IRNAGN	0	Indicates this is the only run by the program.
				1	Indicates another run by the program is to be made. Another set of input data cards must be supplied. The user supplied sub-routines remain the same. The new set of input cards is placed after this card.

APPENDIX F
INPUT AND OUTPUT
PART ONE
USER SUPPLIED PROGRAMS

To use SATANS-III the user must supply 6 programs. The first is a simple 6 card main program that passes control to SATANS.

The second, subroutine GEOM, computes the nondimensional geometry functions of the shell. The correspondence between the nondimensional geometry functions and FORTRAN variables is as follows:

$$\text{DEL} = \Delta = S_T / (a(KMAX-1))$$

$$R(K) = \rho_K = (r/a)_K$$

$$\text{GAM}(K) = \gamma_K = (\rho'/\rho)_K = ((dr/ds)/(r/a))_K$$

$$\text{OMT}(K) = (\omega_\theta)_K = (a/R_\theta)_K$$

$$\text{OMXI}(K) = (\omega_s)_K = (a/R_s)_K$$

$$\text{DEOMX}(K) = (\omega'_s)_K = (a^2 d(R_s^{-1})/ds)_K$$

$$\text{MASS}(K) = \mu_K$$

for K = 1(1)KMAX

The third, subroutine BDB, computes the nondimensional stiffness quantities b , b' , d and d' . Correspondence between the stiffness quantities and FORTRAN variables is as follows:

$$B = b_K = \int E_y d\zeta / ((1-\nu^2)E_o h_o)$$

$$DB = b'_K = a(dB/ds)_K$$

$$D = d_K = \int \zeta^2 E_y d\zeta / ((1-\nu^2)E_o h_o^3)$$

$$DD = d'_K = a(dD/ds)_K$$

The last three subroutines, PLOAD, TLOAD and INITL compute the nondimensional loads applied to the shell, thermal loads applied to the shell and, in the case of a dynamic analysis, the initial conditions on z and $\frac{\partial z}{\partial t}$. Details on these subroutines are given in Refs. 1 and 2.

APPENDIX G contains example input routines for a vibration analysis.

SAMPLE OUTPUT

--PROBLEM NUMBER 7--

CIRCULAR CYLINDRICAL SHELL WITH A LINEARLY VARYING THICKNESS

--INPUT DATA RECORD--

THE BOUNDARY CONDITIONS ARE:

AT THE INITIAL EDGE

-----OMEGA BAR-----				-----LAMDA BAR-----				-----EL-----			
(3.100E 01	3.3	3.3	3.3)	NS	+	(3.3	0.0	0.0	0.0)
(0.0	0.0	0.0	0.0)	CS		(0.0	0.0	0.0	0.0)
(3.0	3.3	0.0	0.0)	PHIS		(0.0	0.0	0.0	0.0)
=											

AT THE FINAL EDGE

-----OMEGA BAR-----				-----LAMDA BAR-----				-----EL-----			
(3.100E 01	3.3	3.3	3.3)	NS	+	(3.3	0.0	0.0	0.0)
(0.0	0.0	0.0	0.0)	CS		(0.0	0.0	0.0	0.0)
(3.0	3.3	0.0	0.0)	PHIS		(0.0	0.0	0.0	0.0)
=											

NUMBER OF STATIONS-----27
MAXIMUM NUMBER OF ITERATIONS-----100
NUMBER OF VIBRATION ANALYSES-----1
CONVERGENCE CRITERION (EIGENVALUES)-----0.1000E-05

CHARACTERISTIC SHELL DIMENSION-----0.1000E 01
REFERENCE THICKNESS-----3.1000E 01
REFERENCE ELASTICITY-----0.1000E 01
REFERENCE STIFFNESS-----0.1000E 01
REFERENCE TIME-----0.1000E 02
POISSON'S RATIO-----0.3000E 00

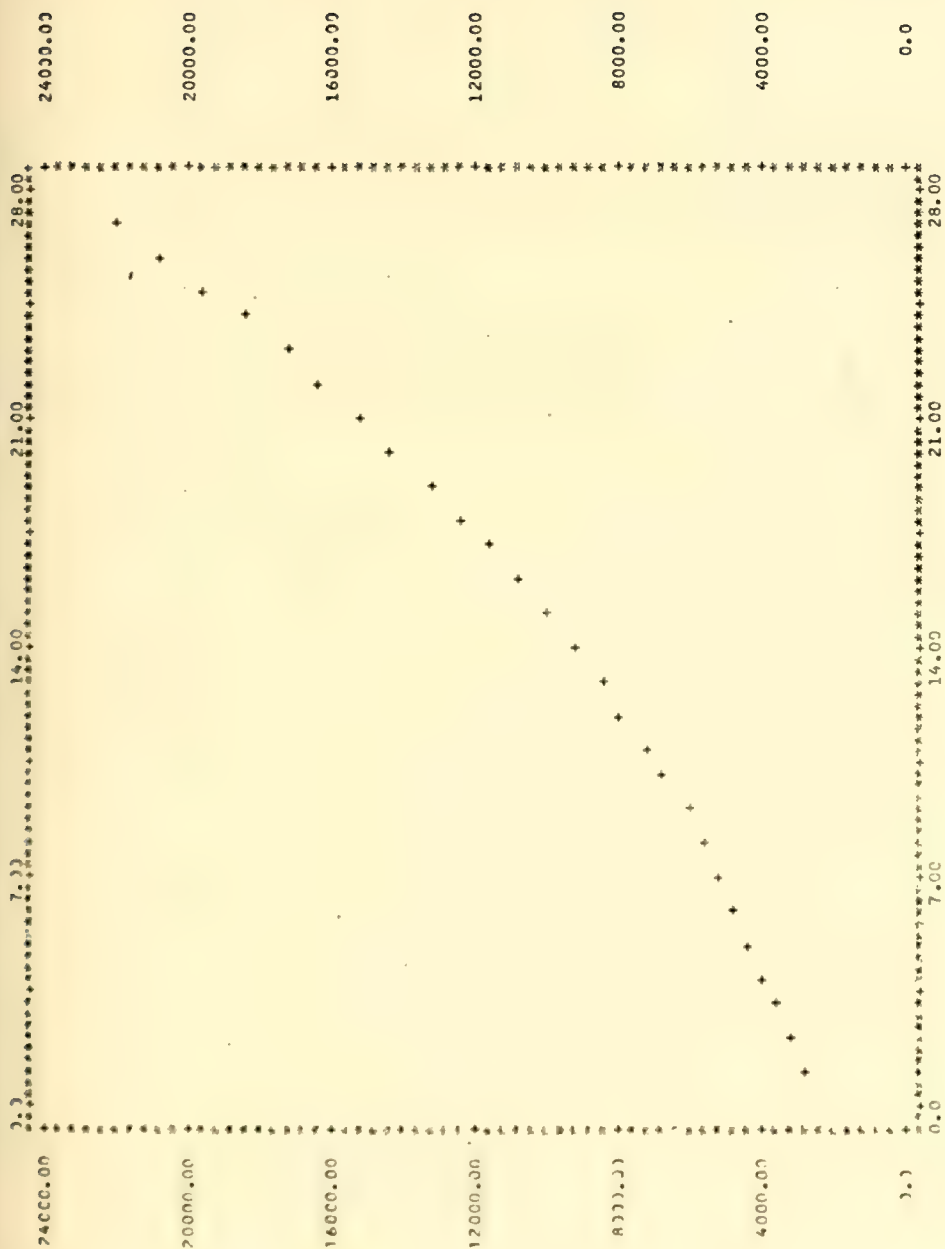
PLOTS HAVE BEEN REQUESTED FOR THE BELOW LISTED GEOMETRY, STIFFNESS OR LOADING QUANTITIES:
D-STIFFNESS

PLOTS HAVE BEEN REQUESTED FOR THE BELOW LISTED MODAL QUANTITIES:
M

THE DATA PRINTED IS DIMENSIONAL
EXECUTING IN SUBROUTINE "DYNAMIC"

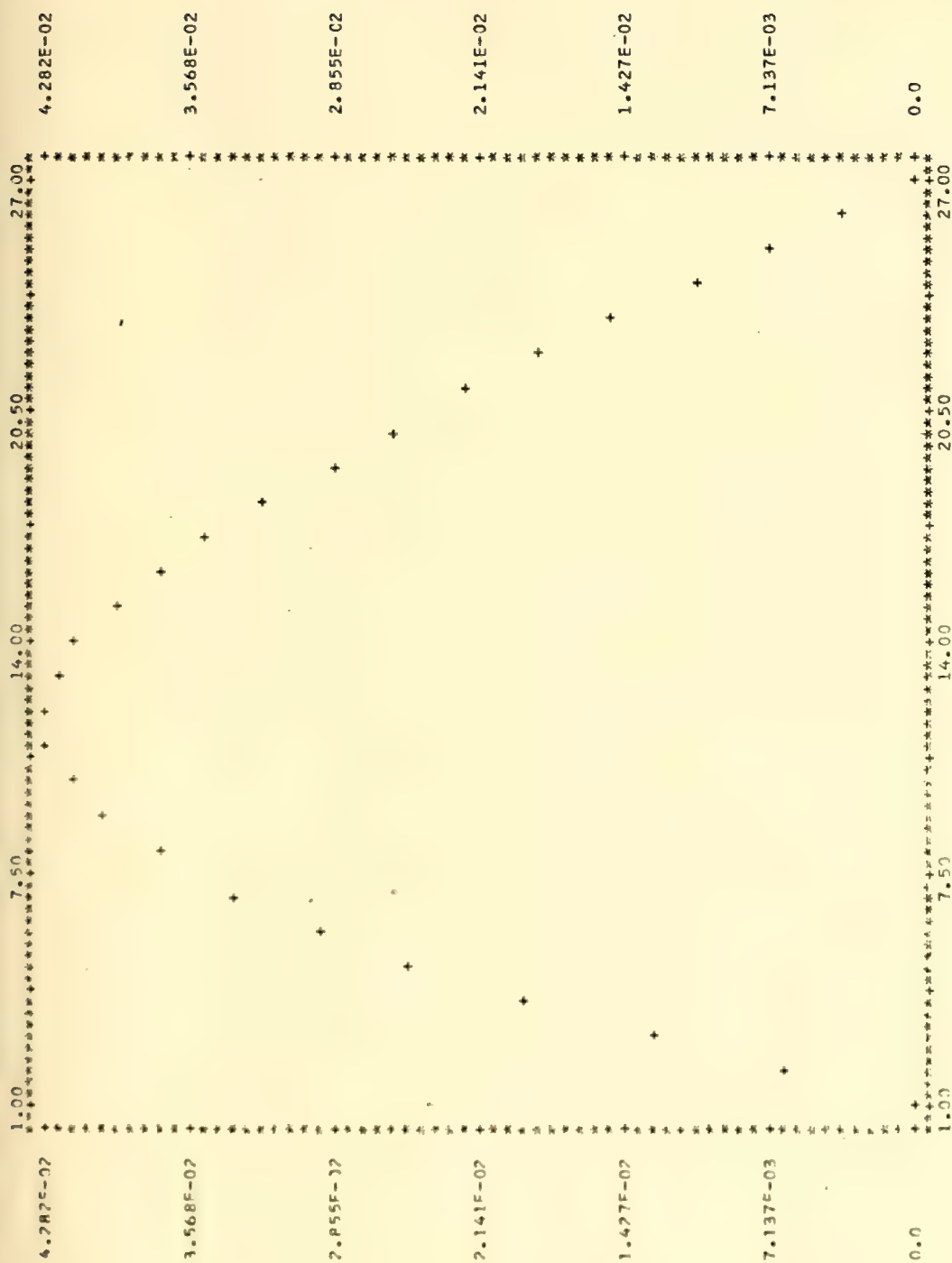
STATION	RADIUS	GAMMA	OMEGA S	OMEGA THETA	DEOMEGA S	MASS
1	1.000E-03	0.000	0.000	1.000E-01	0.000	0.7330E-04
2	1.000E-03	0.000	0.000	1.000E-01	0.000	0.7612E-04
3	1.000E-03	0.000	0.000	1.000E-01	0.000	0.7894E-04
4	1.000E-03	0.000	0.000	1.000E-01	0.000	0.8176E-04
5	1.000E-03	0.000	0.000	1.000E-01	0.000	0.8458E-04
6	1.000E-03	0.000	0.000	1.000E-01	0.000	0.8740E-04
7	1.000E-03	0.000	0.000	1.000E-01	0.000	0.9022E-04
8	1.000E-03	0.000	0.000	1.000E-01	0.000	0.9303E-04
9	1.000E-03	0.000	0.000	1.000E-01	0.000	0.9585E-04
10	1.000E-03	0.000	0.000	1.000E-01	0.000	0.9867E-04
11	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1015E-03
12	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1043E-03
13	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1071E-03
14	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1099E-03
15	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1128E-03
16	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1156E-03
17	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1184E-03
18	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1212E-03
19	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1240E-03
20	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1268E-03
21	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1297E-03
22	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1325E-03
23	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1353E-03
24	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1381E-03
25	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1410E-03
26	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1438E-03
27	1.000E-03	0.000	0.000	1.000E-01	0.000	0.1466E-03

STATION	B STIFFNESS	D STIFFNESS	B PRIME	D PRIME
1	329670E	274725E	1.09890E	0.274725E
2	342350E	307658E	1.109890E	0.318616E
3	355029E	343127E	1.109890E	0.341780E
4	367709E	381228E	1.109890E	0.365757E
5	380388E	422222E	1.109890E	0.390548E
6	393068E	463563E	1.109890E	0.416151E
7	405747E	512182E	1.109890E	0.442569E
8	418427E	561714E	1.109890E	0.469783E
9	431107E	610164E	1.109890E	0.497837E
10	443787E	670154E	1.109890E	0.526635E
11	456466E	729274E	1.109890E	0.556338E
12	469145E	791763E	1.109890E	0.586838E
13	481825E	857683E	1.109890E	0.618131E
14	494505E	927196E	1.109890E	0.650234E
15	507185E	1000328E	1.109890E	0.683154E
16	519864E	1154274E	1.109890E	0.716885E
17	532544E	1332434E	1.109890E	0.751422E
18	545223E	1522863E	1.109890E	0.822957E
19	557903E	1722863E	1.109890E	0.857937E
20	570583E	1938622E	1.109890E	0.897713E
21	583263E	2165331E	1.109890E	0.936340E
22	595943E	2403381E	1.109890E	0.975760E
23	608623E	2653381E	1.109890E	0.101570E
24	621303E	2915777E	1.109890E	0.105704E
25	633983E	3190777E	1.109890E	0.109890E
26	646663E	3478449E	1.109890E	0.109890E
27	659343E	3778977E	1.109890E	0.109890E



X-SCALE: "H"= 0.350E 00 UNITS
Y-SCALE: "H"= 0.400E 03 UNITS
P-STIFFNESS VS STATION

EXECUTING IN SUBROUTINE VIBERS
PERFORMING FREE VIBRATION ANALYSES



X-SCALE: "H"= 0.325E 0) UNITS
Y-SCALE: "H"= 0.714E-03 (UNITS)
NORMAL DEFLECTION VS STATION

APPENDIX G

EXAMPLES OF USER SUPPLIED SUBROUTINES

AND

A LISTING OF SATANS-III

```

C THIS PROGRAM SERVES AS THE 'MAIN' PROGRAM, AND CALLS 'SATANS',
C AND CHECKS 'IRNAGN' TO THE IF WE DESIRE ANOTHER RUN
C COMMON /BLRUN/ IRNAGN
C
1 CALL SATANS
  IF (IRNAGN.EQ.1) GO TO 1
  CALL FLYNVY
  STOP
  END

```



```

C** SUBROUTINE BDB(K,B,DB,D,DD)
C**
C** THIS SUBROUTINE COMPUTES THE NONDIMENSIONAL
C** IN-PLANE AND BENDING STIFFNESS OF THE SHELL.
C**
C** REAL NU,LAM,LAM2,JAY,MT,LSD18,LSDIN
C** COMMON /BL15/ NU,UI(10),VI(10),W1(10),V2(10),W2(10),U3(10),
C** 1 V3(10),W3(10)
C**
C** COMMON /BL17/ DEL
C** COMMON /BL32/ TKN,ELAST,CHAR,SIGO
C**
C** B(K) = (E * H)/((1.-NU**2) * (E(0)H(0)))
C** D(K) = (E * H**3)/(12. * (1.-NU**2) * E(0)H(0)**3)
C**
C** NU
C** = 3
C** E
C** = .3E8
C** X
C** = 2
C** S
C** = DEL * FLOAT(K-1)
C** H
C** = 1*(X-1.)/300.
C** SLOPE
C** = S*SLOPE + 1
C** B
C** = (E*H)/((1.-NU**2)*ELAST*TKN)
C** LB
C** = (E*SLOPE*CHAR)/((1.-NU**2)*ELAST*TKN)
C** D
C** = (E*H**3)/((1.-NU**2)*12.*ELAST*TKN**3)
C** DD
C** = (E*(H**2)*SLOPE*CHAR)/((1.-NU**2)*4.*ELAST*TKN**3)
C** RETURN
C** END

```

```

C** SUBROUTINE PLOAD(K)
C**
C** THIS SUBROUTINE ESTABLISHES THE NON-DIMENSIONAL FOURIER
C** COEFFICIENTS OF THE LOADS APPLIED TO THE SHELL
C**
C** COMMON /IBL1/ MNMAX
C** COMMON /IBL2/ NN(10),MNINIT
C** COMMON /IBL4/ KMAX,KL
C** COMMON /IBL8/ LSTEP,ITR
C** COMMON /BL3/ PR(10),PX(10),PT(10)
C** COMMON /BL6/ SCE,OSE,ALCAD
C** COMMON /BL8/ R(200),GAM(200),OMT(200)
C** COMMON /BL32/ TKN,ELAST,CHAR,SIGO
C** COMMON /BL102/ DELCAD
C** COMMON /BL103/ MASS(200)
C**
C** RETURN
C** END

```



```

SUBROUTINE TLOAD(K)
C THIS SUBROUTINE DESCRIBES THE THERMAL LOADING ON THE SHELL
C
REAL NU
COMMON /IBL1/ MNMAX
COMMON /IBL2/ NN(10), MNINIT
COMMON /IBL3/ NSTEP, ITR
COMMON /IBL4/ TT(10), EMT(10), DMT(10)
COMMON /IBL5/ SOE, DSE, ALPCAD
COMMON /IBL6/ NU, U1(10), V1(10), W1(10), V2(10), W2(10), U3(10),
1 V3(10), W3(10)
COMMON /IBL32/ TKN, ELAST, CHAR, SIGC
RETURN
END

```

```

SUBROUTINE INITL
C THIS SUBROUTINE DESCRIBES THE INITIAL CONDITIONS FOR DYNAMIC CASES
C
      IMPLICIT LOGICAL*1 (5)
      COMMON /IBL1/ MJMAX
      COMMON /IBL2/ NN(10), MNINIT
      COMMON /IBL4/ KMAX, KL
      COMMON /IBL9/ MAXM
      COMMON /IBL12/ KMAX1, KMAX2, NCONV
      COMMON /IBL6/ SOE, AL, AD
      COMMON /IBL32/ TKN, ELAST, CHAR, SIGO
      COMMON /IBL100/ TEEC, $DYMC
      COMMON /IBL101/ DELSD
      COMMON /IBL104/ Z(4,220), ZDOT(4,220), X(4,200), Z0(4,220), Z2(4,220),
1      Z3(4,220)
      RETURN
END

```


SATANS-III LISTING

THE SUBROUTINES ARE LISTED, READING ACROSS, AS FOLLOWS:

NAME	CARD NUMBER	NAME	CARD NUMBER	NAME	CARD NUMBER	NAME	CARD NUMBER
SATANS	10	STATIC	2540	DYNMAC	5610	VIBERS	8680
PMATRX	9240	XANDZ	11560	FORCE	14270	HJ	15890
FFG	16610	ABC	17670	PANDC	18000	MODES	18370
POLE	19360	INLPOL	20880	FNLPOL	21560	PHIBET	22210
TEAETA	23110	UPDATE	24140	OUTPUT	24520	PLOT1	28340
PLOT2	29410	PLOTIT	31380	SCALIT	31950	ROUND	32740
DRAWIT	33220	RANGER	34720	ADJUST	35540	BTTM	36590
TOPPER	37370	ITREFL	38050	ITRATE	38520	ITCPLX	41130
INITAA	42000	VEGOUT	43060	START	44780	MATINV	45150
		FLYINVY	46560				

```

SUBROUTINE SATANS
C THIS SUBROUTINE READS ALL DATA, PRINTS THE OUTPUT TITLE PAGE,
C AND PASSES CONTROL TO ONE OF THE MAJOR CONTROLLING SUBROUTINES
C IMPLICIT LOGICAL*1 ($)
REAL*8 EPSVIB, EPSVEC, EPSAIT
REAL*4 NU, LAM, LAM2, JAY, NT, LSD18, LSDIN, MASS
COMMON /IBL1/ MNMAX
COMMON /IBL4/ KMAX, KL
COMMON /IBL5/ IBCINL, IBCENL
COMMON /IBL7/ MNMAXC, MAXD(10), MAXS(10), MAXSY(10), IS(10,10),
1 JS(10,10), ID(10,10), JD(10,10), IJS(10)
COMMON /IBL9/ MAXM
COMMON /IBL10/ IFREQ, NTHMAX

```



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107 FORMAT (I2)
108 FORMAT (I5,4F1.0,F16.3,I5)
109 FORMAT (3I5,3F15.8)
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SUBROUTINE STATIC
C *****
C THIS SUBROUTINE IS THE MAJOR CONTROLLING ROUTINE FOR ALL STATIC
C ANALYSIS PROBLEMS. IT CONDUCTS INITIALIZATION, PREPARES INPUT
C MATERIAL FOR PLOTTING IF REQUIRED, DETERMINES SHELL GEOMETRY, STIFF-
C NESSES, LOADING (PHYSICAL AND/OR THERMAL), AND INITIAL CONDITIONS.
C IT CONTROLS PROBLEM SOLUTION PROCEDURE.
C *****
IMPLICIT LOGICAL*1 ($)
REAL*4 NU,LAM,LAM2,JAY,MT, LSD18,LSDIN,MASS
COMMON /IBL1/ NMAX
COMMON /IBL2/ 'N' APPEARS AS 'NN' IN SUBROUTINES PLOAD & EFG
C
COMMON /IBL3/ NO,M1,M2,M3
COMMON /IBL4/ KMAX,KL
COMMON /IBL5/ IBCINL,IBCENL
COMMON /IBL6/ KLL
COMMON /IBL7/ NMAXO,MAXD(10),MAXS(10),MAXSY(10),IS(10,10),
1 JS(10,10),ID(10,10),JD(10,10),IJS(10,
COMMON /IBL8/ LSTEP,IIR
COMMON /IBL9/ MAXM
COMMON /IBL10/ IFRFC,NTHVAX
COMMON /IBL11/ ICCRFL,IPASS
COMMON /IBL12/ KMAX1,KMAX2,NCONV
COMMON /IBL13/ ITRMAX,LMAX
COMMON /BL1/ A(4,4),B(4,4),C(4,4)
COMMON /BL2/ PR(10),PX(10),PT(10)
COMMON /BL3/ P(4,4,200),ZFIM(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
COMMON /BL4/ ZF4M(4,4,10),DT(10),DMT(10)
1 COMMON /BL5/ 'MT' APPEARS AS 'ERT' IN SUBROUTINES INLPOL & FNLPOL
C
COMMON /BL6/ SOE,CSE,ALCAD
COMMON /BL7/ DI,S1
COMMON /BL8/ R(200),GAM(200),DMT(200)
COMMON /BL9/ EFS(4,10),ELIS(4),CEES(4,10)
COMMON /BL10/ PHIX(10),PHIT(10),PHI(10)
COMMON /BL11/ CMXI(200),PHEE,T0,T2
COMMON /BL12/ TDLI,TCEL
COMMON /BL13/ OMEGI(4,4),CAPL1(4,4),OMEGL(4,4),CAPLL(4,4),
1 COMMON /BL14/ UNIT(4,4)
COMMON /BL15/ LAM2,LSD18,LSDIN
COMMON /BL16/ NU,U1(10),V1(10),W1(10),V2(10),U2(10),W2(10),U3(10),
1 V3(10),W3(10)
COMMON /BL17/ EPS
COMMON /BL18/ DEL
COMMON /BL19/ TH(36)
COMMON /BL20/ DECMX(200)

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DO 98 J=1,4
KKLM=J/4+1
OMGL(I,J)=OMGL(I,J)*SIGT(KKLM)
CAPLI(I,J)=CAPLI(I,J)*SIGC(KKLM)
14 IF (IBCFNL.LT.0) GO TO 17
DO 99 I=1,4
CC=99 J=1,4
KKLM=J/4+1
OMGL(I,J)=OMGL(I,J)*SIGT(KKLM)
CAPLI(I,J)=CAPLI(I,J)*SIGC(KKLM)
17 LAM=TKN/CHAR
SOF=SIGD/ELAST
CSE=.5*SCE
CI=1.0-NU
SI=1.0+NU
LM2=LAM*2
1F(NDIMEN.LT.1) GO TO 228
SIGC=1.0
ELAST=1.0
TKN=1.0
CHAR=1.0
DO 230 M=1,MAXM
N(M)=0.0
PX(M)=0.0
PT(M)=0.0
PR(M)=0.0
TT(M)=0.0
MT(M)=0.0
DMT(M)=0.0
MAXD(M)=0
MAXS(M)=0
MAXSY(M)=0
CALL GFCM
1 ICHK1=IABS(IGAMMA)+IABS(IOMEGS)+IABS(IOMEGT)+IABS(IDEOMS)
+IABS(IRADII)
1 ICHK2=IABS(IBSTIF)+IABS(DDSTIF)+IABS(DDSTF)
IF (.NOT.$PLOTS) GO TO 11
DO 2 K=1,KMAX
XSTATN(K)=FLOCAT(K)
2 IF (ICCHK1.EQ.0) GO TO 11
DO 1 K=1,KMAX
XRADII(K)=R(K)*CHAR
YGAMMA(K)=GAM(K)/CHAR
YOMEGS(K)=CMXI(K)/CHAR
YOMEGT(K)=DMT(K)/CHAR
YDEOMS(K)=DEOMX(K)/(CHAR*CHAR)
1 CONTINUE

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11 CONTINUE
86 DO 86 K=1,KMAX
   MASS(K)=0.
   WRITE(6,802)
   DO 978 K=1,KMAX
     RKK=R(K)*CHAR
     CMXIK=CMXI(K)/CHAR
     GAMK=GAM(K)/CHAR
     CMTK=OMT(K)/CHAR
     DEOMXK=DEOMX(K)/(CHAR*CHAR)
978   WRITE(6,803) K,RKK,GAMK,CMXIK,CMTK,DEOMXK
805   MO=0
      M1=0
      M2=0
      M3=0
      ABN=CHAR/SIGC/TKN
      ZN=SIGC*TKN
      WRITE(6,112)
      DO 888 K=1,KMAX
        CALL BDB(K,B,DB,D,DD)
        RST=ELAST*TKN
        ZST=ELAST*TKN*3
        B=B*BST
        C=C*ZST
        DB=CB/CHAR*BST
        CC=OD/CHAR*ZST
      WRITE(6,71) K,B,D,CB,DD
      IF (.NOT.$PLOTS.CR.(ICHECK2.EQ.0)) GO TO 888
      YBSTIF(K)=B
      YCSTIF(K)=D
      YRBSIF(K)=DB
      YCDSTIF(K)=DD
888   CCNTINUE
      CALL PLOAD(1)
      CALL TLOAD(1)
      DO 889 M=1,MNMAX
        WRITE(6,113) N(M)
        WRITE(6,114)
          ICHK3=IABS(IPR)+IABS(IPT)+IABS(ITT)+IABS(IMT)
          +IABS(IDTT)+IABS(IDMT)
1      DO 890 K=1,KMAX
        CALL PLOAD(K)
        CALL TLOAD(K)
        PRM=PR(M)/ABN
        PTM=PT(M)/ABN
        PXM=PX(M)/ABN
        TIM=TT(M)*ZN
        EMTM=MT(M)/CHAR*ZN*TKN

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DTM=DT(M)/CHAR*ZN
DMTM=DMT(M)*ZN*TKN*(CHAR*CHAR)
WRITE (6,115) K,PRM,PXM,PTM,TTM,EMTM,DTM,DMTM
IF (.NOT.$PLOTS.OR.(ICHCK3.EQ.0)) GO TO 890
YPS(K)=PRM
YPS(K)=PXM
YPT(K)=PTM
YTT(K)=TTM
YMT(K)=EMTM
YCTT(K)=DTM
YCMT(K)=DMTM
CONTINUE
890 IF (M.EQ.1) ICHCK3=ICHCK1+ICHCK2+ICHCK3
IF ($PLOTS.AND.(ICHCK3.GT.0)) CALL PLOT1(M)
CONTINUE
DELSQ=DELL*#2
TDLI=.5/DEL
TDEL=2.0*DEL
MNINIT=1
MMAXO=MNMAX
DO 20 I=1,4
DO 20 J=1,4
UNIT(I,J)=0.0
UNIT(I,J)=1.0
20 IF (I.EQ.J) UNIT(I,J)=1.0
NMAX=MAXM*KMAX2
DO 22 K=1,NMAX
DO 22 I=1,4
ZCOT(I,K)=0.0
ZC(I,K)=0.0
Z2(I,K)=0.0
Z3(I,K)=0.0
Z(I,K)=0.0
22 ALQAD=DELOAD
CALL PMATRX
LSTEP=1
LCHANG=0
ICORFL=0
IF (MNMAX.EQ.MAXM) ICORFL=1
IPASS=0
CALL XANDZ
IF (ITRMAX.EQ.1) GO TO 50
NMMAXO=MNMAX
IF (IPASS.LT.2) CALL MODES
IF (INCNV.EQ.1).AND.(ITR.GT.1) GO TO 50
IF (ITR.LT.ITRMAX) GO TO 23
IF (LCHANG.LT.LCHMAX) GO TO 30
WRITE (6,220) NO

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50 GO TO 500
   FL=LSSTEP
   LI=IPRINT/IPRINT
   FLI=LI
   FI=FLI-FL/FI
   IF (FI.EQ.0.) CALL OUTPUT(IMODE)
   IF (LSSTEP.EQ.1) ITR=1
   IF (LSSTEP.EQ.1) ITRPR=1
   IF (ITR.GT.ITRPR) ITRPR=ITR
   IF (LSSTEP.GE.LSMAX) GO TO 360
60 DO 61 MN=1,MNMAX
   IK=K+(MN-1)*KMAX2
   DO 61 I=1,4
   ZN=2.0*Z(I,IK)-ZO(I,IK)
   ZO(I,IK)=ZN
61 IF (LSSTEP.GE.LSMAX) GO TO 360
62 ALOAD=ALOAD+DELOAD
   LSTEP=LSTEP+1
   ITR=1
   GO TO 400
360 WRITE(6,221) NO
23 GO TO 500
   ITR=ITR+1
30 GO TO 400
310 IF (LSTEP-1) 310,310,320
   WRITE(6,223)
320 GO TO 500
   WRITE(6,222)
   LCHANG=LCHANG+1
   LSTEP=LSTEP-1
   ALOAD=ALOAD-DELOAD
   DELOAD=DELOAD/5.0
   DO 32 MN=1,MNMAX
   DO 32 K=1,KMAX2
   IK=K+(MN-1)*KMAX2
   DO 32 I=1,4
   ZO(I,IK)=ZO(I,IK)
   GO TO 62
C *****
71 FORMAT(20X,13,4X,4E20,6)
112 FORMAT(///17X,12H STATION 20H B STIFFNESS 20H D ST
113 IF STRESS 20H D PRIME
113 FORMAT(///25X,44HPRESSURE AND TEMPERATURE COEFFICIENTS FOR N=13,8H
1 FOLLOWING)
114 FORMAT(5X,7HSTATION,3X,15H
15H PX 15H

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1 PT      15H      TT      MT      15H      DTT      1
25H DMT      //)
115 FORMAT(6X,13.7X,7E15.4) THE MAXIMUM NUMBER OF LOAD CHANGES HAVE BE
220 FORMAT(1H1,80H END PROBLEM NUMBER I4) THE MAXIMUM NUMBER OF LOAD STEPS HAVE BEEN
221 FORMAT(1H1,79H END PROBLEM NUMBER I4) THE MAXIMUM NUMBER OF LOAD STEPS HAVE BEEN
222 1 TAKEN. END PROBLEM NUMBER I4) THE SOLUTION DID NOT CONVERGE WITHIN THE M
222 1 MAXIMUM NUMBER OF ITERATIONS. THE LOAD FACTOR HAS BEEN DIVIDED BY
25.)
223 FORMAT(1H1,69H THE SOLUTION DID NOT CONVERGE FOR THE FIRS
223 1T LOAD INCREMENT.//11X,71HLOOK FOR AN ERROR IN THE INPUT DATA, OR T
223 2RY A SMALLER VALUE FOR DELTA.)
802 FORMAT(1H1,17X,15H STATION 16H RADIUS 16H DEOMEGA S //)
803 16H OMEGA S 16X,5E16.4)
8888 FORMAT ('0,120, EXECUTING IN SUBROUTINE "STATIC"')
500 RETURN
END

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SUBROUTINE DYNAMIC
C THIS SUBROUTINE IS ONE OF THE MAJOR CONTROLLING SUBROUTINES FOR
C ALL DYNAMIC ANALYSIS PROBLEMS. IT OPERATES IN A FASHION SIMILAR
C TO SUBROUTINE STATIC.
C IMPLICIT LOGICAL*1 ($)
C REAL*4 NU,LAM,LAM2,JAY,MT,LSD18,LSD1N,MASS
C COMMON /IBL1/ MNMAX
C COMMON /IBL2/ N(10),MNIN,IT
C COMMON /IBL3/ MO,M1,M2,M3
C COMMON /IBL4/ KMAX,KL
C COMMON /IBL5/ IBCINL,I BCENL
C COMMON /IBL6/ KLL
C COMMON /IBL7/ MNMAXO,MXO(10),MAXS(10),MAXSY(10),IS(10,10),
1 JS(10,10),ID(10,10),JD(10,10),IJS(10,
C COMMON /IBL8/ LSTEP,IT
C COMMON /IBL9/ MAXM
C COMMON /IBL10/ IPRREC,NTRMAX
C COMMON /IBL11/ I CORREL,IPASS
C COMMON /IBL12/ KMAX1,KMAX2,NCONV
C COMMON /IBL13/ ITRMAX,LSMAX
C COMMON /BL1/ A(4,4),BE(4,4),C(4,4)
C COMMON /BL3/ PR(10),PK(10),PT(10)
C COMMON /BL4/ P(4,4,200),ZF1M(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
1 ZF4M(4,4,10)

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COMMON	/BL5/	TT(10),MT(10),DT(10),DMT(10)	5880
COMMON	/BL6/	MT,APPEARS AS 'EMT' IN SUBROUTINES INLPOL & FNLPOL	5890
COMMON	/BL7/	SOE,OSE,ALOAD	5900
COMMON	/BL8/	D1,S1	5910
COMMON	/BL9/	R(200),SAM(200),DMT(200)	5920
COMMON	/BL10/	FFS(4,10),ELIS(4),GEES(4,10)	5930
COMMON	/BL11/	PHIX(10),PHIT(10),PHI(10)	5940
COMMON	/BL12/	OMXI(200),PHEE,T0,T2	5950
COMMON	/BL13/	TCLI,TDEL	5960
COMMON	/BL14/	OMEGI(4,4),CAPLI(4,4),OMEGL(4,4),CAPLL(4,4),	5970
COMMON	/BL15/	UNIT(4,4)	5980
COMMON	/BL16/	LAM2,LSQ18,LSQ19	5990
COMMON	/BL17/	NU,UI(10),V1(10),W1(10),V2(10),U2(10),W2(10),U3(10),	6000
COMMON	/BL18/	V3(10),W3(10)	6010
COMMON	/BL19/	EPS	6020
COMMON	/BL20/	DEL	6030
COMMON	/BL21/	ELL(4),ELL(4)	6040
COMMON	/BL22/	TH(36)	6050
COMMON	/BL23/	DEOMX(200)	6060
COMMON	/BL24/	JAY(4,4),H(4,4)	6070
COMMON	/BL25/	DG(4,4,10),DL(4,4,10),DF(4,4,10)	6080
COMMON	/BL26/	E(4,4),F(4,4),G(4,4)	6090
COMMON	/BL27/	BX3(10),DTT(10),BXT3(10),BE3(10)	6100
COMMON	/BL28/	EXX3(10),ETX3(10),EX3(10),EX3(10),ET3(10)	6110
COMMON	/BL29/	BX1(10),B1(10),BXT1(10),BEL(10),BX2(10),BT2(10),	6120
COMMON	/BL30/	BXT2(10),BE2(10)	6130
COMMON	/BL31/	EXX1(10),ETX1(10),ETX1(10),ET1(10),EXX2(10),	6140
COMMON	/BL32/	ETX2(10),ETX2(10),EX2(10),ET2(10)	6150
COMMON	/BL33/	DELSQ,EXT1(10)	6160
COMMON	/BL34/	TKN,ELAST,CHAR,SIGO	6170
COMMON	/BL35/	DEE(4,4,200),DST(4,4,200)	6180
COMMON	/BL36/	TEEC,\$DYNMC	6190
COMMON	/BL37/	DELOAD	6200
COMMON	/BL38/	MASS(200)	6210
COMMON	/BL39/	Z(4,220),ZDOT(4,220),X(4,200),Z(4,220),Z2(4,220),	6220
COMMON	/BL40/	Z3(4,220)	6230
COMMON	/BL41/	TX(10),TTH(10),MX(10),MTH(10),MXT(10),	6240
COMMON	/BL42/	CS(10)	6250
COMMON	/BL43/	ABZ,ABZN,AEZ3,DD2	6260
COMMON	/BL44/	IPRAGI,ICAMMA,ICOMEGS,ICOMEGT,IDEOMS,IBSTIF,IDSTIF,	6270
COMMON	/BL45/	IPBSTIF,IDDSTF,IPR,IPS,IPT,ITT,IMT,IDTT,IMDT,INS,	6280
COMMON	/BL46/	INTH,INSTH,IOS,IMS,IMTH,IMSTH,IU,IV,IW,IPHS,	6290
COMMON	/BL47/	IPHT,IPH1,\$PLOGIS,\$MODAL	6300
COMMON	/BL48/	XPRACI(100),YCAMMA(100),YCOMEGS(100),YCOMEGT(100),	6310
COMMON	/BL49/	YDECHS(100),YBSTIF(100),YDSTIF(100),YB8STF(100),	6320
COMMON	/BL50/	YDCSTF(100),YPR(100),YPS(100),YPT(100),YTT(100),	6330
COMMON	/BL51/	YMT(100),YDTT(100),YDMT(100),YNS(100),YNTH(100),	6340
COMMON	/BL52/		6350


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4      YNSTH(100),YQS(100),YMS(100),YMTN(100),YMSTH(100),
5      YU(100),YV(100),YW(100),YPHIS(100),YPHIT(100),
6      YPHI(100),XSTATN(100)
COMMON /BLK1/ VMAS,NN2,$VIBES
DIMENSION SIGT(2),SIGC(2),TITLE(18)
DIMENSION VBAR(10),AVR(10)
WRITE (6,8888)
DELSO=DELOAD#DELOAD
KL=KMAX-1
KLL=KMAX-2
KMAX1=KMAX+1
KMAX2=KMAX+2
AK=KL
SIGT(1)=SIGC*TKN
SIGT(2)=SIGC/ELAST
SIGC(1)=SIGC*CHAR/ELAST
SIGC(2)=SIGC*TKN**3/CHAR
IF (18CINL.LT.0) GO TO 14
DO 98 I=1,4
DO 98 J=1,4
KKLM=J/4+1
CMEGL(I,J)=OMEG(I,J)*SIGT(KKLM)
CAPL(I,J)=CAPL(I,J)*SIGC(KKLM)
98      IF (18CFNL.LT.0) GO TO 17
DO 99 I=1,4
DO 99 J=1,4
KKLM=J/4+1
CMEGL(I,J)=CMEGL(I,J)*SIGT(KKLM)
CAPL(I,J)=CAPL(I,J)*SIGC(KKLM)
99      LAM=TKN/CHAR
SCE=SIGC/ELAST
OSF=.5#SCE
OI=1.0-NU
SI=1.0+NU
LAM2=LAM**2
IF (NDIMEN.LT.1) GO TO 228
SIGC=1.0
ELAST=1.0
TKN=1.0
CHAR=1.0
DO 230 M=1,MAXM
N(M)=0.0
PX(M)=0.0
PT(M)=0.0
PR(M)=0.0
TT(M)=0.0
228

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6840 MT(M)=0.0
6850 CT(M)=0.0
6860 DMT(M)=0.0
6870 MAXD(M)=0
6880 MAXS(M)=0
6890 MAXSY(M)=0
6900 CALL GEOM
6910 ICHCK1=IABS(IGAMMA)+IABS(IOMEGS)+IABS(IOMEGT)+IABS(IDEOMS)
6920 ICHCK2=IABS(IRADII)+IABS(IGAMMA)+IABS(IOMEGS)+IABS(IOMEGT)+IABS(IDEOMS)
6930 ICHCK2=IABS(IRSTIF)+IABS(IDSTIF)+IABS(IBBSTF)+IABS(IDDSTF)
6940 IF (.NOT. $PLOTS) GO TO 11
6950 DO 2 K=1,KMAX
6960 XSTATN(K)=FLOAT(K)
6970 IF (ICHCK1.EQ.0) GO TO 11
6980 DO 1 K=1,KMAX
6990 XRADII(K)=R(K)*CHAR
7000 YGAMMA(K)=GAM(K)/CHAR
7010 YOMEGS(K)=CMXI(K)/CHAR
7020 YOMEGT(K)=CMT(K)/CHAR
7030 YDECHS(K)=DEOMX(K)/(CHAR*CHAR)
7040 CONTINUE
7050 ICHCK1=0
7060 WRITE(6,810)
7070 IF (NDIMEN.EQ.1) TEED=1.0
7080 DO 979 K=1,KMAX
7090 RKK=R(K)*CHAR
7100 CMXIK=CMXI(K)/CHAR
7110 GAMK=GAM(K)/CHAR
7120 CMTK=CMT(K)/CHAR
7130 CFCMXK=DEOMX(K)/(CHAR*CHAR)
7140 AMSS=MASS(K)*TEED*TKN/CHAR**2
7150 WRITE(6,813) K,RKK,GAMK,CMXIK,CMTK,DEOMXK,AMSS
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WRITE (6,71) K,B,D,DB,DD
IF (.NOT.$PLOTS.OR.(ICHCK2.EQ.0)) GO TO 888
YBSTIF(K)=8
YDSTIF(K)=D
YB8STIF(K)=DB
YDDSTIF(K)=DD
CCNT INUE
CALL PLOAD(1)
CALL TLOAD(1)
DELSO=DEL*2
TDLI=.5/DEL
TDEL=2.0*DEL
MUNIT=1
MNMNAXO=MNMNAX
DO 20 I=1,4
DO 20 J=1,4
UNIT(I,J)=0.0
IF(I.EQ.J) UNIT(I,J)=1.0
NMAX=MAXM*KMAX2
ICHCK3.=ICHCK1 + ICHCK2
IF($PLOTS.AND.(ICHCK3.GT.0)) CALL PLOT1(1)
IF($VIBES) CALL VIBERS(8500)
DO 22 K=1,NMAX
DO 22 I=1,4
ZDOT(I,K)=0.0
ZQ(I,K)=0.0
Z2(I,K)=0.0
Z3(I,K)=0.0
Z4(I,K)=0.0
IF(ICH.EQ.0) GO TO 834
CALL INITL
ACQ=CHAR*SIGO/ELAST
ACM=SIGO*TKN*.3/CHAR
DO 830 M=1,MNMAX
NM=(M-1)*KMAX2
WRITE(6,126) N(M)
WRITE(6,127)
DO 831 K=2,KMAX1
MK=K+MM
TU=ACQ*ZQ(1,MK)
TV=ACQ*ZQ(2,MK)
TW=ACQ*ZQ(3,MK)
TM=ACM*ZQ(4,MK)
KK=K-1
831 WRITE(6,71) KK,TU,TV,TW,TM
WRITE(6,129)
DO 830 K=2,KMAX1
ACD=CHAR*SIGO/(ELAST*TM=EO)

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AMD=SIGO*TKN**3/(CHAR*TEEO)
MK=K+MM
TU=ACD*ZDOT(1,MK)
TV=ACD*ZDOT(2,MK)
TW=ACD*ZDOT(3,MK)
TM=AMD*ZDOT(4,MK)
KK=K-1
WRITE(6,71) KK,TU,TW,TM
DO 830 I=1,4
  Z(I,MK)=ZO(I,MK)+ZDCT(I,MK)*DELOAD
  Z2(I,MK)=ZO(I,MK)-ZDCT(I,MK)*DELOAD
  Z3(I,MK)=ZO(I,MK)-2.*ZDCT(I,MK)*DELOAD
830 CCNTINUE
834 ALCAD=1.0
  CALL PMATRX
  LSTEP=1
  LCHANG=0
  ITR=1
  ICORFL=J
  IF(MNMAX.EQ.MAXM) ICORFL=1
  IPASS=0
  CALL XANDZ
  IF(ITRMAX.EQ.1) GO TO 50
  MNMAXO=MNMAX
  IF(IPASS.LT.2) CALL MODES
  IF(NCONV.EQ.1) GO TO 50
  IF(ITR.LT.ITRMAX) GC TO 23
  GO TO 365
50 FL=LSTEP
  FI=IPRINT
  LI=LSTEP/IPRINT
  FLI=LI-FL/FI
  FT=FLI-FL/FI
  IF(FT.EQ.0.) CALL OUTPUT(IMODE)
  IF(LSTEP.EQ.1) ITR=1
  IF(LSTEP.EQ.1) ITRPR=1
  IF(ITR.GT.ITRPR) ITRPR=ITR
  IF(LSTEP.GE.LSMAX) GO TO 360
  DO 65 MN=1,MNMAXO
  DO 65 K=1,KMAX2
    IK=K+(MN-1)*KMAX2
    DO 65 I=1,4
      ZN=3.0*(Z(I,IK)-ZO(I,IK))+Z2(I,IK)
      Z3(I,IK)=Z2(I,IK)
      Z2(I,IK)=ZO(I,IK)
      ZO(I,IK)=Z(I,IK)
      Z(I,IK)=ZN
    ALCAD=1.0
65

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LSTEP=LSTEP+1
ITR=1
GO TO 400
ITR=ITR+1
23 GO TO 400
360 WRITE(6,271) (AVB(M),M=1,MAXM)
WRITE(6,188) ITRPR
GO TO 500
365 IF(LSTEP.EQ.1) GO TO 367
WRITE(6,266) ITRMAX,LSTEP,NQ
WRITE(6,188) (AVB(M),M=1,MAXM)
GO TO 500
367 WRITE(6,273)
GO TO 500
C *****
71 FORMAT(20X,I3,4X,4E2C,6)
112 FORMAT(///,17X,12H STATION 20H B STIFFNESS 20H D ST
113 IFPRIME 20H D PRIME //)
126 FORMAT(///,5X,29H THE INITIAL CONDITIONS FOR N=I3,8H FOLLOW//)
127 FORMAT(19X,7H STATION,3X,20H U M S U DOT 20H V DOT
129 FORMAT(///,15X,7H STATION,3X,20H W U DOT M S DOT 20H V DOT
188 FORMAT(///, THE MAXIMUM VBAR FOR EACH MODE IS,10E11,4)
189 FORMAT(///, THE MAXIMUM NUMBER OF ITERATIONS TAKEN IS ,14)
266 FORMAT(1H,35H THE SOLUTION DID NOT CONVERGE IN I3,24H ITERATIONS
271 AT TIME STEPS 5,21H. END PROBLEM NUMBER I4,1H.)
271 FORMAT(1H,79H THE MAXIMUM NUMBER OF TIME STEPS HAVE BEEN
273 TAKEN. END PROBLEM NUMBER I4)
273 FORMAT(1H,69H THE SOLUTION DID NOT CONVERGE FOR THE FIRST
IT TIME INCREMENT,11X,71H LOAD.)
273 A SMALLER VALUE FOR DELTA,1X,15H STATION 16H RADIUS 16H GAMMA
810 FORMAT(1H,5X,15H STATION 16H DEOMEGA S 16H
1 MASS //)
813 FORMAT(8X,I3,9X,6E16,6)
8683 FORMAT(10,120,EXECUTING IN SUBROUTINE "DYNAMIC")
500 RETURN
END

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SUBROUTINE VIBERS(4)
C *****
C THIS IS THE MAJOR CONTROLLING SUBROUTINE FOR THE FREE VIBRATION
C ANALYSIS PORTION OF THE PROGRAM. THE MODE OF OPERATION (FREQUENCY
C RANGE SEARCH, SUPPLIED POINTS, MINIMUM EIGENVALUE) IS
C DETERMINED AND APPROPRIATE SUBROUTINES CALLED.

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C *****
IMPLICIT LOGICAL=1 (S)
REAL*8 EPSVIB, EPSVEC, EPSAIT, TWOPI, WV, XV, YV
COMMON /IBL2/ N(10), MNINIT
COMMON /IBL7/ MNMAXO, MAXX(10), MAXSY(10), MODVIB(3,100), ITEM
1P(110)
COMMON /BL100/ TEEC, $DYNMC
COMMON /BL101/ DELSD
COMMON /BL104/ WV(4,203), XV(4,203), YV(4,203), FILL(28), SHFTPT(3,100)
COMMON /BLK2/ IVIBES, IVB
COMMON /BLK3/ TWOPI, IBEGIN, IEND, IGO, ISTOP
COMMON /BLK5/ $FLAG, $TAG, $DOVEC
COMMON /BLK6/ EPSVIB, EPSVEC, EPSAIT
COMMON /BLK9/ ITR1, ITR2
COMMON /BLK10/ ASHIFT, ASHFUM, ATSHF, BII, TOLUP, TOLDWN, TOLCLS
C *****
WRITE(6,9999)
DELSO=1.0
IF(EPSVIB.LT.(1.0-08)) CALL VECOUT(3,&6)
6 IF(ITR1.LE.3) CALL VECOUT(2,&5)
DO 4 IVB=1,IVIBES
KEY1=MODVIB(1,IVB)
N(1)=MODVIB(2,IVB)
$DOVEC=.FALSE.
IF(MODVIB(3,IVB).EQ.1) $DOVEC=.TRUE.
IF(KEY1.EQ.4) CALL RANBER(&4)
IF(KEY1.EQ.1.AND.KEY1.LE.3) CALL VECOUT(6,&1)
SHFTPT(1,IVB)=0.0
$DOVEC=.TRUE.
KEY1=1
CALL VECOUT(5,&1)
DO 3 J=1,KEY1
1 ASHIFT=-(SHFTPT(J,IVB)+SNGUL(TWOPI)*TEEO)**2)
WRITE(6,8888) ASHIFT,SHFTPT(J,IVB)
K=J
IF(ASHIFT.EQ.(0.0)) K=1
CALL START(K)
CALL PMATRIX
CALL ITRREAL(&2)
CALL ITCPLX(&3)
GO TO 3
2 CALL VECOUT(9,&3)
3 CONTINUE
4 CONTINUE
5 RETURN
C *****
8888 FORMAT('0',52X,'SHIFT POINT IS',E14.6/66X,'(,E14.6,' HZ,')')
9999 FORMAT('///51X,'EXECUTING IN SUBROUTINE VIBERS'//49X,'PERFORMING

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1FREE VIBRATION ANALYSES'////)
END

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SUBROUTINE PMATRIX
C***
C*** THIS SUBROUTINE CALLS THE SUBROUTINES HJ(K,MN), EFG(K,MN), ABC,
C*** AND PANDD(K,MN) TO SET UP THE P, P-BAR AND P-HAT MATRICES GIVEN
C*** BY EQUATIONS (30) OF REFERENCE (2).
C*** INTERNALLY, MATRICES DL, DG AND DF ARE SET UP FOR THE CALCULA-
C*** TION OF X(1) GIVEN BY EQUATION (31A) OF REF. (2), WHERE
C***
C*** X(1) = DL*SMALL-L(1) + DG*SMALL-G(1) + DF*SMALL-F(1)
C***
C*** THE SPECIAL P MATRIX FOR A SHELL WITH AN INITIAL POLE IS ALSO
C*** COMPUTED HERE. ZF2M, ZF3M, ZF4M ARE SET UP FOR THE CALCULATION OF
C*** Z(K+1) GIVEN BY EQUATION (31B) OF REF. (2), WHERE
C***
C*** Z(K+1)=ZF1M*SMALL-L(K) + ZF2M*X(K) + ZF3M*X(K-1) + ZF4M*SMALL-F
C*** IF THE SHELL HAS A FINAL POLE, THE MATRICES CL0,CL1,CL2 ARE
C*** PREPARED FOR THE CALCULATION OF Z(K)
C***
C*** IMPLICIT LOGICAL*1 ($)
C***
C*** REAL JAY
C*** COMMON /IBL1/ MNMAX
C*** COMMON /IBL2/ N(10), MNINIT
C*** COMMON /IBL3/ NO,M1,M2,M3
C*** COMMON /IBL4/ KMAX,KL
C*** COMMON /IBL5/ IBCINL,IBCFNL
C*** COMMON /IBL1/ A(4,4,200),BEE(4,4),C(4,4)
C*** COMMON /IBL4/ P(4,4,200),ZF1M(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
C*** ZF4M(4,4,10)
C*** COMMON /IBL13/ OMEGL(4,4),CAPL1(4,4),OMEGL(4,4),CAPLL(4,4),
C*** UNIT(4,4)
C*** COMMON /IBL23/ JAY(4,4),H(4,4)
C*** COMMON /IBL24/ DG(4,4,10),DL(4,4,10),DF(4,4,10)
C*** COMMON /IBL25/ E(4,4),F(4,4),G(4,4)
C*** COMMON /IBL104/ Z(4,220),ZDOT(4,220),X(4,200),ZO(4,220),Z2(4,220),
C*** Z3(4,220)
C*** COMMON /IBLK1/ VMAS,NN2,SVIBES
C*** COMMON /IBLK10/ ASHIFT,ASHFUN,ATSHF,BII,TOLUP,TOLDWN,TOLCLS
C*** DIMENSION PATA(4,4),PBTE(4,4),POTA(4,4),DLL(4,4),PTR(4,
C*** 14),DGG(4,4),ZF1(4,4),ZF2(4,4),ZF3(4,4),ZF4(4,4),G1(4,
C*** 2T(4),INDEX(4,2),CL0(4,4),CL1(4,4),CL2(4,4),G1(4,
C*** EQUIVALENCE (CL0(1),ZF1M(1)),(CL1(1),ZF2M(1)),(CL2(1),ZF3M(1)),
C*** 1(ZFPO(1),PATA(1)),(ZFPI(1),PBTA(1)),(ZFPP2(1),POTA(1))
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2.(ZF1(1),DLL(1)),(ZF2(1),PTR(1))
  ASHFUM = ASHFIFT
  ATSHF = ASHFUM
  IF(IBC(INL,LT,0) GO TO 10
  DO 1 MN=MNINIT,MNMAX
  CALL HJ(1,MN)
  CALL EFG(1,MN)
  CALL ABC
  CALL MATINV(C,4,G1,0,DETERM,IPIVOT,INDEX,4,ISCALE)
  DO 3 I=1,4
  DO 3 J=1,4
  SUMA=0.
  SUMB=0.
  SUMC=0.
  SUMJ=0.
  DO 4 L=1,4
  SUMJ=SUMJ+OMEG1(I,L)*JAY(L,J)
  SUMA=SUMA+C(I,L)*A(L,J)
  SUMB=SUMB+C(I,L)*BEE(L,J)
  SUMC=SUMC+OMEG1(I,L)*H(L,J)
  PATA(I,J)=SUMA+UNIT(I,J)
  PBTA(I,J)=SUMB
  PCJA(I,J)=SUMC
  PCJA(I,J)=SUMJ
  DO 5 I=1,4
  DO 5 J=1,4
  SUMCB=0.
  SUMCA=0.
  SUMCC=0.
  DO 6 L=1,4
  SUMCB=SUMCB+POTA(I,L)*PATA(L,J)
  SUMCA=SUMCA+POTA(I,L)*PBTA(L,J)
  SUMCC=SUMCC+POTA(I,L)*PCJA(L,J)
  DLL(I,J)=SUMCB+PJTA(I,J)+CAPLI(I,J)
  PTR(I,J)=SUMCA
  EGG(I,J)=SUMCC
  CALL MATINV(DLL,4,PTR,4,DETERM,IPIVOT,INDEX,4,ISCALE)
  DO 1 I=1,4
  DO 1 J=1,4
  SUMD=0.
  SUME=0.
  DO 7 L=1,4
  SUMD=SUMD+DLL(I,L)*DGG(L,J)
  SUME=SUME-DLL(I,L)*CMEG1(L,J)
  DO(I,J,MN)=SUMD
  IF($VIPES) GO TO 2
  CF(I,J,MN)=SUME

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      2 1 P(I,J,MN)=CLL(I,J)
      10 DO 11 MN=MNINIT,MNMAX
          NN=IABS(N(MN))
          IJ=1+KMAX*(MN-1)
          DO 14 I=1,4
              X(I,IJ)=0.
              DO 14 J=1,4
                  P(I,J,IJ)=0.
                  IF(NN.GT.3) GO TO 11
                  IF(NN.GT.2) GO TO 90
                  IF(NN.GT.1) GO TO 12
                  IF(NN.GT.0) GO TO 13
                  P(3,3,IJ)=-1.
                  P(4,4,IJ)=-1.
                  NO=MN
                  GO TO 11
              12 P(4,4,IJ)=-1.
                  GO TO 11
              90 M3=MN
                  GO TO 11
              13 P(1,1,IJ)=-1.
                  P(2,1,IJ)=1.
                  IF(N(MN).LT.0) P(2,1,IJ)=-1.
                  MI=MN
                  CC=INT(INUE
              11 KLAST=KMAX
              20 IF(I8CFNL.LT.0) KLAST=KL
                  DO 23 K=2,KLAST
                      CC 23 MN=MNINIT,MNMAX
                      CALL EFG(K,MN)
                      CALL ABC
              23 CALL PANDD(K,MN)
                  IF(I8CFNL.LT.0) GO TO 30
                  DO 40 MN=MNINIT,MNMAX
                      IKL=MN*KMAX-1
                      JKL=KMAX*MN
                      CALL HJ(KMAX,MN)
                      DO 41 I=1,4
                          DO 41 J=1,4
                              SUMQ=0.
                              SUMJ=0.
                              DO 42 L=1,4
                                  SUMQ=SUMQ+OMEG(L,I,L)*H(L,J)

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SUMP=SUMP+P(I,L,IKL)*P(L,J,JKL)
SUMJ=SUMJ+OMEG(L,I,L)*JAY(L,J)
PATA(I,J)=SUMO
PBTA(I,J)=UNIT(I,J)-SUMP
PJTA(I,J)=SUMJ+CAPLL(I,J)
DO 43 I=1,4
DO 43 J=1,4
SUMOP=0.
SUMJP=0.
SUMOM=0.
DO 44 L=1,4
SUMOP=SUMOP+PATA(I,L)*PBTA(L,J)
SUMJP=SUMJP+PJTA(I,L)*P(L,J,JKL)
SUMOM=SUMOM-PATA(I,L)*P(L,J,IKL)
ZF1(I,J)=SUMOP-SUMJP
ZF2(I,J)=SUMOM-PJTA(I,J)
CALL MATINV(ZF1,4,ZF2,4,DETERM,IPIVOT,INDEX,4,ISCALE)
DO 45 I=1,4
DO 45 J=1,4
SZF3=0.
SZF4=0.
DO 46 L=1,4
SZF3=SZF3+ZF1(I,L)*PATA(L,J)
SZF4=SZF4-ZF1(I,L)*OMEG(L,L,J)
ZF3M(I,J,MN)=SZF3
ZF4M(I,J,MN)=SZF4
ZF1M(I,J,MN)=ZF1(I,J)
ZF2M(I,J,MN)=ZF2(I,J)
CONTINUE
RETURN
DO 31 MN=MNINI T, MNMAX
IKL=VN*KMAX-1
NN=IABS(I(MN))
IF(NN.GT.3) GO TO 31
IF(NN.GT.2) GO TO 30
IF(NN.GT.1) GO TO 33
IF(NN.GT.0) GO TO 34
NO=MN
DO 35 J=1,4
DO 35 I=1,4
CLO(I,J)=0.
ZFP0(I,J)=0.
ZFP0(1,1)=1.
ZFP0(2,2)=1.
ZFP0(3,1)=P(3,1,IKL)
ZFP0(3,2)=P(3,2,IKL)
ZFP0(3,3)=P(3,3,IKL)+1.
ZFP0(3,4)=P(3,4,IKL)

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ZFP0(4,1)=P(4,1,IKL)
ZFP0(4,2)=P(4,2,IKL)
ZFP0(4,3)=P(4,3,IKL)
ZFP0(4,4)=P(4,4,IKL)+1.
CLO(4,3)=1.
CLO(4,4)=1.
CALL MATINV(ZFP0,4,CLO,4,DETERM,IPIVOT,INDEX,4,ISCALE)
GO TO 31
300 M3=MN
34 GO TO 31
M1=MN
DO 60 J=1,4
  I=1,4
  CL1(I,J)=0.
  ZFP1(I,J)=P(1,1,IKL)+1.
  ZFP1(I,1)=P(1,2,IKL)
  ZFP1(I,2)=P(1,3,IKL)
  ZFP1(I,3)=P(1,4,IKL)
  ZFP1(I,4)=P(1,4,IKL)
  ZFP1(2,1)=1.
  ZFP1(2,2)=-1.
  IF(N(MN).LT.0) ZFP1(2,2)=1.
  ZFP1(3,3)=1.
  ZFP1(4,4)=1.
  CL1(1,1)=1.
  CALL MATINV(ZFP1,4,CL1,4,DETERM,IPIVOT,INDEX,4,ISCALE)
GO TO 31
33 M2=MN
DO 70 J=1,4
  I=1,4
  CL2(I,J)=0.
  ZFP2(I,J)=P(4,1,IKL)
  ZFP2(I,1)=P(4,2,IKL)
  ZFP2(I,2)=P(4,3,IKL)
  ZFP2(I,3)=P(4,4,IKL)+1.
  CL2(4,4)=1.
  CALL MATINV(ZFP2,4,CL2,4,DETERM,IPIVOT,INDEX,4,ISCALE)
31 CONTINUE
  RETURN
  END

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COMMON /BL29/ BX1(10),BT1(10),EXT1(10),BEL(10),BX2(10),BT2(10),
1 COMMON /BL30/ BX12(10),BE2(10),
COMMON /BL31/ EXX1(10),ET1(10),EX1(10),ET1(10),EXX2(10),
1 COMMON /BL32/ EXT2(10),EXT2(10),EX2(10),ET2(10)
COMMON /BL33/ DELSQ,EXT1(10)
COMMON /BL34/ TEEQ,$DYNMC
COMMON /BL35/ DELOA
COMMON /BL36/ MASS(200)
COMMON /BL37/ Z(4,220),ZDOT(4,220),X(4,200),ZO(4,220),Z2(4,220),
1 COMMON /BL38/ Z3(4,220)
1 DIMENSION ELLS(4),CL1(4,4),CL2(4,4)
1 CLO(4,4),CL1(4,4),ZDO(4)
1 TZMAXX(4,10),ZDO(4)
2 TZMAXX(4,10),ZDO(4)
EQUIVALENCE (CLO(1),ZF1M(1)),(CL1(1),ZF2M(1)),(CL2(1),ZF3M(1))
C***
DO 201 I=1,4
DO 201 M=1,MNMAX
NJ=1+((M-1)*KMAX2
TZMAX(I,M)=ABS(Z(I,NJ))
DO 201 K=2,KMAX2
KM=K+(M-1)*KMAX2
AZTST=ABS(Z(I,KM))
IF(AZTST.GT.TZMAX(I,M)) TZMAX(I,M)=AZTST
201 CONTINUE
IF(ITRMAX.EC.1) GO TO 66
DO 1 M=1,MNMAX
I=1+(KMAX+2)*(M-1)
U1(M)=Z(1,I)
V1(M)=Z(2,I)
W1(M)=Z(3,I)
I1=I+1
U2(M)=Z(1,I1)
V2(M)=Z(2,I1)
W2(M)=Z(3,I1)
1 IF(18CINL.LT.0) GO TO 100
CALL PHIBET(1)
DO 2 M=1,MNMAX
BX1(M)=BX3(M)
BT1(M)=BT3(M)
BX11(M)=BX13(M)
BT11(M)=BT13(M)
PE1(M)=BE3(M)
CALL TEAETA(1)
DO 3 M=1,MNMAX
EXX1(M)=EXX3(M)
ET11(M)=ETT3(M)
ETX1(M)=ETX3(M)

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EXT1(M)=EXT3(M)
EX1(M)=EX3(M)
EXT1(M)=ET3(M)
CALL PHIBET(2)
DO 4 M=1,MNMAX
  SX2(M)=SX3(M)
  BX2(M)=BX3(M)
  BF2(M)=BE3(M)
  CALL TEAETA(2)
DO 5 M=1,MNMAX
  EXX2(M)=EXX3(M)
  ETX2(M)=ETX3(M)
  EXT2(M)=EXT3(M)
  EX2(M)=EX3(M)
  ET2(M)=ET3(M)
  CALL PHIBET(3)
  CALL TEAETA(3)
CONTINUE
IF(IBCINL.LT.0) GO TO 20
CALL BDR(1,B1,DB,D,CD)
GAM1=GAM(1)
CALL TLOAD(1)
DO 8 M=1,MNMAX
  IF(ITRMAX.EQ.1) GO TO 67
  FFS(1,M)=-TT(M)*ALOAD+USE*(BX1(M)+BE1(M)+NU*(BT1(M)+BE1(M))*B1
  FFS(2,M)=OSE*(B1+C1)*BX1(M)+ET1(M)
  FFS(3,M)=LAM2*GAM1*DI*VT(M)*ALOAD-(EXX1(M)+ETX1(M))*SOE
  GO TO 8
FFS(1,M)=-TT(M)*ALCAD
FFS(2,M)=0
FFS(3,M)=LAM2*GAM1*DI*VT(M)*ALOAD
FFS(4,M)=0
DO 9 I=1,4
  EL1S(I)=ALOAD*EL1(I)
CALL FORCE(1)
CALL FORCE(2)
DO 10 K=3,KLL
  KP=K+1
  IF(ITRMAX.EQ.1) GO TO 10
  CALL UPDATE
  CALL PHIBET(KP)
  CALL TEAETA(KP)
  CALL FORCE(K)
  IF(ITRMAX.NE.1) CALL UPDATE
  IF(IBCINL.LT.0) GO TO 120
  IF(ITRMAX.EQ.1) GO TO 11

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11 CALL PHIBET(KMAX)
   CALL TEAETA(KMAX)
   CALL FORCE(KL)
   CALL FORCE(KMAX)
12 DO I=1,4
   ELLS(I)=ALOAD*ELL(I)
   CALL BC8(KMAX,BL,CB,D,DD)
   GAML=GAM(KMAX)
   FLS(4)=0.
   CALL TLOAD(KMAX)
   DO I=1,MNMAX
   IF(M.GT.1) ELLS(I)=0.0
   IF(ITRMAX.EQ.1) GO TO 68
   FLS(1)=-TT(M)*ALOAD+USE*(BX3(M)+BE3(M)+NU*(BT3(M)+BE3(M))*BL
   FLS(2)=-TT(M)*ALOAD+USE*(BX3(M)+EX3(M)+ET3(M))
   FLS(3)=L*AM2*GAML*DI*MT(M)*ALOAD-(EXX3(M)+ETX3(M))*SOE
   GO TO 69
68 FLS(1)=-TT(M)*ALCAD
   FLS(2)=0.
   FLS(3)=L*AM2*GAML*DI*MT(M)*ALOAD
69 CONTINUE
   IK=KL+KMAX*(M-1)
   L=M*KMAX*M
   DO I=1,4
   SUMZ=0.
   DO J=1,4
   THE FOLLOWING CARD CAUSES BOUNDARY CONS TO EXIST FOR MODE 'O' ONLY
   IF(M.NE.1) ELLS(J)=0
   15 SUMZ=SUMZ+ZF1M(I,J,M)*ELL(J)
   14 Z(I,L)=SUMZ
   LS=1
150 DO I=1,MNMAX
   DO L=LS,KMAX
   K=KMAX2-L
   KPX=K-1
   KZ=K+1
   IJ=KPX+(M-1)*KMAX
   JK=KZ+(M-1)*KMAX2
   KK=JK-1
   DO I=1,4
   SUMZ=0.
   DO J=1,4
   18 SUMZ=SUMZ-P(I,J,IJ)*Z(J,JK)
   SUMZ=SUMZ+X(I,IJ)

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17 ASUMZ=ABS(SUMZ)
16 IF(ASUMZ.GT.1.E+15) ITR=ITRMAX
   IF(NCONV.NE.1.OR.ASUMZ.LT.1.E-05) GO TO 17
   DELZ=ABS(Z(I,KK))-SUMZ
   ZTEST=EPS*TZMAX(I,M)
   IF(DELZ.GT.ZTEST) NCONV=0
   Z(I,KK)=SUMZ
   CONTINUE
   IF(IBCINL.LT.0) GO TO 30
   DO 25 M=1,MNMAX
   CALL EFG(I,M)
   CALL ABC
   IJ=2+(M-1)*KMAX2
   IJ1=IJ+1
   IJ2=IJ-1
   DO 21 I=1.4
   SUMZ=0.
   CO 22 J=1.4
   SUMZ=SUMZ-A(I,J)*Z(J,IJ1)-BEE(I,J)*Z(J,IJ)
   Z(I,I)=SUMZ+GEES(I,M)
   CALL MATINV(C,4,ZT,1,DETERM,IPIVOT,INDEX,4,ISCALE)
   DO 23 I=1.4
   Z(I,IJ2)=ZT(I)
   CCNTINUE
   RETURN
   CALL INLPOL
   DO 101 V=1,MNMAXC
   U1(M)=U2(M)
   V1(M)=V2(M)
   W1(M)=W2(M)
   IJ=3+KMAX2*(M-1)
   U2(M)=Z(1,IJ)
   V2(M)=Z(2,IJ)
   W2(M)=Z(3,IJ)
   GO TO 102
   IF(ITRMAX.NE.1) CALL FNLPOL
   CALL FORCE(KL)
   IF(M2.EQ.0) GO TO 122
   L=KL+(M2-1)*KMAX
   LI=KMAX1+(M2-1)*KMAX2
   DO 130 I=1.4
   SUM=0.
   CC 131 J=1.4
   SUM=SUM+CL2(I,J)*X(J,L)
   ASUMZ=ABS(SUM)
   IF(NCONV.NE.1.OR.ASUMZ.LT.1.E-05) GO TO 130
   DELZ=ABS(Z(I,LI))-SUM
   ZTEST=EPS*TZMAX(I,M2)

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130 IF(DELZ.GT.ZTEST) NCONV=0
122 Z(I,LI)=SUM
    IF(MI.EQ.0) GO TO 123
    L=KL+(MI-1)*KMAX
    LI=KMAX1+(MI-1)*KMAX2
    DO 132 I=1,4
        SUM=0.
        DO 133 J=1,4
            SUM=SUM+CL1(I,J)*X(J,L)
        ASUMZ=ABS(SUM)
        IF(NCONV.NE.1 .OR. ASUMZ .LT. 1.E-05) GO TO 132
        DELZ=ABS(Z(I,LI)-SUM)
        ZTEST=EPS*ZMAX(I,MI)
        IF(DELZ.GT.ZTEST) NCONV=0
123 Z(I,LI)=SUM
123 IF(MI.EQ.0) GO TO 124
    L=KL+(MI-1)*KMAX
    LI=KMAX1+(MI-1)*KMAX2
    DO 134 I=1,4
        SUM=0.
        DO 135 J=1,4
            SUM=SUM+CL0(I,J)*X(J,L)
        ASUMZ=ABS(SUM)
        IF(NCONV.NE.1 .OR. ASUMZ.LT.1.E-06) GO TO 134
        DELZ=ABS(Z(I,LI)-SUM)
        ZTEST=EPS*ZMAX(I,MI)
        IF(DELZ.GT.ZTEST) NCONV=0
134 Z(I,LI)=SUM
124 LS=2
    GO TO 150
    END

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SUBROUTINE FORCE(K)
C *** THIS SUBROUTINE COMPUTES THE GEE VECTOR IN EQUATION (28) OF
C REF. 2, AND THE X VECTOR IN EQUATION (29A) OF REF. 2 FOR A GIVEN MER-
C TIONAL STATION K. THE VECTOR 'GEES' IS THE NONLINEAR VALUE OF 'GEE' *
C AT STATION 1. ***
C *** IMPLICIT LOGICAL*1 ($) ***
    REAL NU,MT,LAM2,MAS,MAS
    COMMON /IBL1/ MNMAX
    COMMON /IBL2/ N(10),MNIN:T
    COMMON /IBL4/ KMAX,KL
    COMMON /IBL8/ LSTEP,ITR
    COMMON /IBL12/ KMAX1,KMAX2,NCONV
    COMMON /IBL13/ ITRMAX,LSMAX

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CCCOMMON /BL3/ PR(10),PX(10),PT(10)
CCCOMMON /BL4/ P(4,4,200),ZF1N(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
1 ZF4M(4,4,10)
CCCOMMON /BL5/ TT(10),MT(10),DT(10),DMT(10)
CCCOMMON /BL6/ SOE,OSE,ALOAD
CCCOMMON /BL7/ DI,SI
CCCOMMON /BL8/ R(200),GAM(200),DMT(200)
CCCOMMON /BL9/ FFS(4,10),ELIS(4),GLIS(4,10)
CCCOMMON /BL11/ CMXI(200),PHEE,TO,T2
CCCOMMON /BL12/ TDL1,TDEL
CCCOMMON /BL14/ LAM2,LSDI8,LSDI9
CCCOMMON /BL15/ NU,UI(10),V1(10),V2(10),W1(10),W2(10),U2(10),U3(10),
1 V3(10),W3(10)
CCCOMMON /BL17/ DEL
CCCOMMON /BL24/ DG(4,4,10),DL(4,4,10),DF(4,4,10)
CCCOMMON /BL27/ PX3(10),BT3(10),BT3(10),BE3(10)
CCCOMMON /BL28/ EXX3(10),ETT3(10),ETX3(10),EXT3(10),EX3(10),ET3(10)
CCCOMMON /BL29/ BXT1(10),BT1(10),BXT1(10),BE1(10),BX2(10),BT2(10),
1 BXT2(10),BE2(10)
CCCOMMON /BL30/ EXX1(10),ETT1(10),ETX1(10),EX1(10),ET1(10),EXX2(10),
1 ETT2(10),ETX2(10),EXT2(10),EX2(10),ET2(10)
CCCOMMON /BL31/ CELSO,EXT1(10)
CCCOMMON /BL34/ CELSO(4,4,200),DST(4,4,200)
CCCOMMON /BL100/ TEEC,$DYNMC
CCCOMMON /BL101/ DELSD
CCCOMMON /BL102/ DELLOAD
CCCOMMON /BL103/ MASS(200)
CCCOMMON /BL104/ Z(4,220),ZDCT(4,220),X(4,200),ZO(4,220),Z2(4,220),
1 Z3(4,220)
C** DIMENSION GEE(4)
FDIFF(A,B,C)=(-1.5*A+2.2-.5*C)/DEL
RS=R(K)
RR=1./RS
GA=GAM(K)
CX=CMXI(K)
DT=DMT(K)
CL2=DI+LAM2
CALL BDB(K,BS,DBS,D,DD)
CALL PLOAD(K)
CALL TLOAD(K)
YAS=MASS(K)
DO 4 M=1,MNMAX
IZ=K+1+(M-1)*KMAX
IK=K+(M-1)*KMAX
IK1=IK-1
ENR=EN*RR
ENR=EN*RR

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DET X=-FDIFF(ETX2T,ETX2(M),ETX1(M))
GO TO 7
8 CBX=TDLI*(BX3(M)-BX1(M))
  CBT=TDLI*(BT3(M)-BT1(M))
  CBF=TDLI*(BF3(M)-BF1(M))
  CBXT=TDLI*(BXT3(M)-BXT1(M))
  CFT=TDLI*(FT3(M)-FT1(M))
  DEXX=TDLI*(EX3(M)-EX1(M))
  DEXX=TDLI*(EXX3(M)-EXX1(M))
  DETX=TDLI*(ETX3(M)-ETX1(M))
  BT2T=BT2(M)
  PX2T=PX2(M)
  BE2T=BE2(M)
  EXX2T=EXX2(M)
  ET2T=ET2(M)
  ETX2T=ETX2(M)
  EX2T=EX2(M)
  ET2T=ET2(M)
  GEE(1)=GEE(1)+ENR*(BX+DBE+GA*Q1*(BX2T-BT2T)+NU*(DBT+DBE)
    +ENR*(BT2T+BE2T))-2.*OX*
  GEE(2)=GEE(2)+CSE*(BT2T+ETX2T)-ENR*(EXX2T+ETX2T))*TDEL
    (DBXT+2.*GA*BXT2T))-D1*(BT2T+BE2T))-D1*
  GEE(3)=GEE(3)+OSE*(BT2T+BE2T))+2.*(GA*(EXX2T+ETX2T)+DEXX+DET X+ENR*
    (BT2T+BE2T)))*TDEL
50 IF(K.GT.1) GO TO 10
  IF(M.GT.1) ELIS(1)=0.0
  CO 20 I=1,4
  GEES(I,M)=GEE(I)
  SUMX=0.
  DO 21 J=1,4
  C FOLLOWING CARD CAUSES A SPECIFIED BOUNDARY CONDITION VALUE TO
  C EXIST ONLY FOR MODE 'J'
  C IF (M.NE.1) ELIS(J)=0
  21 SUMX=SUMX+DL(I,J,M)*ELIS(J)+DG(I,J,M)*GEE(J)+DF(I,J,M)*FFS(J,M)
  20 GO TO 4
  10 DO 11 I=1,4
  SUMX=0.
  12 SUMX=SUMX+DEE(I,J,I,K)*GEE(J)-DST(I,J,I,K)*X(J,I,K)
  11 X(I,I,K)=SUMX

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4 CONTINUE
RETURN
END

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SUBROUTINE HJ(K,MN)
C THIS SUBROUTINE COMPUTES THE ELEMENTS OF THE H AND JAY
C MATRICES FOR BOTH RODICARIES OF THE SHELL
C
REAL L2,LAM2,LSDIN, LSD18,JAY,NU
COMMON /IBL2/ N(10),MNINIT
COMMON /IBL4/ KMAX,KL
COMMON /BL6/ R(200),GAM(200),OMT(200)
COMMON /BL11/ QMXI(200),PHEE,TO,t2
COMMON /BL14/ LAM2,LSD18,LSDIN
COMMON /BL15/ NU,U1(10),V1(10),W1(10),W2(10),U3(10),
1 V3(10),W3(10)
COMMON /BL17/ DEL
COMMON /BL20/ DEOMX(200)
COMMON /BL23/ JAY(4,4),H(4,4)
EQUIVALENCE(L2,LAM2)
CALL BDB(K,B,DB,D,OD)
YAH=1.
IF(K.EQ.1.OR.K.EQ.KMAX)YAH=2.
CI=(1.-NU)
GA=GAM(K)
OX=QMXI(K)
RA=R(K)
EN=N(MN)
ENQ=EN/RA
REG=0.
IF(YAH.EQ.2.) REG=1.
OT=OMT(K)
OXI=3.*OMXI(K)-OMT(K)
OTX=3.*OMT(K)-OMXI(K)
CL=DEL*L2*ENR
H(1,1)=R
H(1,2)=0.
H(1,3)=0.
H(1,4)=0.
H(2,1)=0.
H(2,2)=8.*D1/2.+L2*D*D1/8.*OTX*2*REG
H(2,3)=CL/2.*OTX*REG
H(2,4)=0.
H(3,1)=0.
H(3,2)=CL*OTX*YAH/4.

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ENR2=ENR**2
H(3,3)=L2*D*D1*(YAH*ENR2+(1.+NU)*GA**2)
GA2=GA**2
H(3,4)=L2
H(4,1)=0.
H(4,2)=0.
H(4,3)=-1.
H(4,4)=0.
JAY(1,1)=NU*GA*B
JAY(1,2)=NU*B*ENR
JAY(1,3)=B*(OX+NU*OT)
JAY(1,4)=0.
JAY(2,1)=-B*D1*ENR/2.-DL/8.*CXT*OTX*REG
JAY(2,2)=-GA*H(2,2)
JAY(2,3)=-GA*H(2,3)
JAY(2,4)=0.
JAY(3,1)=-L2*D*D1*((1.+NU)*GA2*OX+ENR2/4.*OXT*YAH)
JAY(3,2)=-GA*DL/2.*(2.*OT*(1.+NU)+OTX/2.*YAH)
JAY(3,3)=-L2*D*D1*((1.+NU+YAH)*GA*ENR2
JAY(3,4)=L2*D1*GA
JAY(4,1)=OX
JAY(4,2)=0.
JAY(4,3)=0.
JAY(4,4)=0.
DO 1 I=1,4
DO 1 J=1,4
1 H(I,J)=H(I,J)/2./DEL
END
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SUBROUTINE EFG(K,MN)
C THIS SUBROUTINE PREPARES THE ELEMENTS OF THE E, F, AND G
C FOR EACH MERIDIAN STATION K AND FOR EACH FOURIER MODE, MN.
C IMPLICIT LOGICAL*1 (I)
REAL NU,N,
LAW2,LSQIN,MASS,MAS
COMMON /BL2/NU(10),MASS,MAS
COMMON /BL8/ R(200),G(200),DMT(200)
COMMON /BL11/ CMXI(200),PHEE,TO,T2
COMMON /BL14/ LAW2,LSQIN,LSQIN
COMMON /BL15/ NU,U(10),V1(10),V2(10),W1(10),W2(10),U3(10),
1 V3(10),V4(10)
COMMON /BL20/ DECMX(200)
COMMON /BL25/ E(4,4),F(4,4),G(4,4)
COMMON /BL100/ TEEQ,AN,ANC
COMMON /BL101/ DELSD
```



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COMMON /BL102/ DELOAD
COMMON /BL103/ MASS(200)
COMMON /BLK1/ VMAS,NN2,$VIBES
C*****
N=NN(MN)
MAS=MASS(K)
VMAS = MAS
IF($VIBES) MAS = 0.0
CALL BDG(K,B,DB,D,CD)
E(1,1)=B
E(1,2)=0.
E(1,3)=0.
E(1,4)=0.
E(2,1)=0.
C1=(1.-NU)
RA=R(K)
GA=GAM(K)
CX=CMXI(K)
CT=ONT(K)
LFX=DEOMX(K)
REX=(3.*CT-OX)
GA2=GA**2
RXE=(3.*OX-OT)
CTX=OT*OX
CNLR=LAM2*D*ND1/(2.*RA)
DDNLR=ONLR*DD/D
E(2,2)=B*CI/2.+LAM2*D*CI*REX**2/8.
E(2,3)=ONLR*REX
E(2,4)=0.
E(3,1)=0.
E(3,2)=E(2,3)
RAN=(N/RA)**2
E(3,3)=LAM2*D*DI*(2.*RAN+(1.+NU)*GA2)
E(3,4)=LAM2
E(4,1)=0.
E(4,2)=0.
E(4,3)=0.
E(4,4)=0.
F(1,1)=GA*B+DB
F(1,2)=(1.+NU)*B*(N/RA)+DNLR*REX*RXE/4.
F(1,3)=B*(OX+NU*CT)+LAM2*D*DI*((1.+NU)*GA2*CX+RAN*RXE/2.)
F(1,4)=LAM2*OX
F(2,1)=-F(1,2)
F(2,2)=(DI/2.)*(GA*B+DB)-(LAM2*D*DI*REX/8.)*(2.*DEX-GA*(5.*OX
1-3.*OT))+LAM2*DD*CI*REX**2/8.
F(2,3)=ONLR*(2.*(1.+NU)*GA*OT-DEX+3.*GA*(CX-OT))+DDNLR*REX
F(2,4)=0.
F(3,1)=-F(1,3)

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17680
17690
17700
17710

```

F(3,2)=DNLR*(3.*GA*CX-GA*OT*(5.+2.*NU)-DEX)+DDNLR*REX
F(3,3)=-LAM2*D*D1*((1.+NU)*(2.*GA*CX*OT+GA**3)+2.*GA*RX)
1+LAM2*D*D1*((1.+NU)*GA2+2.*RX)
F(3,4)=LAM2*GA*(2.-NU)
F(4,1)=D*QX
F(4,2)=0
F(4,3)=-D*NU*GA
F(4,4)=0
G(1,1)=NU*DB*GA-NU*B*OTX-B*GA2-D1*B*RX/2.-LAM2*D*D1*((1.+NU)*GA2*
1CX**2+RX**2*RX/8.)
2-2.*MAS/DELS
G(1,2)=NU*(DEX)
1+(1.+NU)*CX
G(1,3)=B*(DEX+GA*(OX-OT))+DB*(OX+NU*OT)-LAM2*D*D1*GA*RX*(RXE/2.+
11.+NU)*CX
G(1,4)=LAM2*D*D1*GA*CX
G(2,1)=-B*GA*N*(3.-NU)/(2.*RA)-D1*N*DB/(2.*RA)+DNLR*2.*(-1.*(1.+
1NU)*GA*OTX+GA/8.*(6.*OTX-7.*OX**2-3.*OT**2)-DEX/4.*(5.*OT-3.*OX))
2-DDNLR/4.*REX*RXE
G(2,2)=-GA*F(2,2)+D1/2.*B*OTX-B*RX-LAM2*D*D1*((1.+NU)*OT**2*RX
1-OTX/8.*REX**2)
2-2.*MAS/DELS
G(2,3)=-B*N*(OT+NU*CX)/PA+DNLR*(GA*DEX-2.*GA2*OX-2.*(1.+NU)*OT
1*RX+REX*(GA2+OTX))-DDNLR*REX*GA
G(3,1)=-B*GA*(OT+NU*CX)+LAM2*D*D1*(GA*(1.+NU)*(-GA*DEX+GA2*OX
1-OTX*RX+2.*CX*OX)+RX/2.*(GA*OX-GA*OT-3.*DEX))
2-LAM2*D*D1*((1.+NU)*GA2*OX+RX/2.*RXE)
G(3,2)=-B*N*(OT+NU*CX)/PA+DNLR*(2.*(1.+NU)*OTX*OT-GA2*OX+2.*GA2
1*OT-OT*RX)+GA*DEX+3.*GA2*(OT-OTX)+OTX*REX)-DDNLR*(2.*(1.+NU)*GA
2*OT+GA*REX)
G(3,3)=-B*(OX**2+2.*NU*OTX+OT**2)+LAM2*D*D1*RX*((1.+NU)*(OTX-RX
1+2.*GA2)+2.*(GA2+OTX))-LAM2*D*D1*RX*(3.+NU)*GA
2-2.*MAS/DELS
G(3,4)=-LAM2*(D1*OTX+NU*RX)
G(4,1)=D*(DEX+NU*GA*CX)
G(4,2)=D*(DEX+NU*OT/RA
G(4,3)=D*NU*RX
G(4,4)=-1.
RETURN
END

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SUBROUTINE ABC
C
C THIS SUBROUTINE COMPUTES THE ELEMENTS OF THE A, BEE, AND C
C MATRICES.
C

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17980
17990

```

IMPLICIT LOGICAL*1 ($),BEE(4,4),C(4,4)
COMMON /BL1/ A(4,4),TDLI,TDEL
COMMON /BL12/ DEL
COMMON /BL25/ E(4,4),F(4,4),G(4,4)
COMMON /BLK1/ VMASS,NN2,$VIBES
COMMON /BLK10/ ASHIFT,ASHFUM,ATSHF,BII,TOLUP,TCLDWN,TOLCLS
COMMON /BLK11/ CIAG(4)
DIMENSION TEMP(48)
EQUIVALENCE (TEMP(1),A(1,1))
C2=2./DEL
DO 1 I=1,4
DO 1 J=1,4
  CEIJ=D2*E(I,J)
  FIJ=F(I,J)
  BEE(I,J)=-2.*DEIJ+TDEL*C(I,J)
  C(I,J)=DEIJ-FIJ
1  A(I,J)=DEIJ+FIJ
  IF(.NOT.$VIBES) GO TO 4
  VMASS=1./O(TDEL*VMASS)
  DO 2 I=1,48
  2  TEMP(I)=VMASS
  DO 3 I=1,4
  3  BEE(I,I)=BEE(I,I)-A*HFUM*C(I,I)
  CONTINUE
  4  END

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SUBROUTINE PANDD(K,MN)
** THIS SUBROUTINE COMPUTES THE ELEMENTS OF THE P, P-BAR, AND
** P-HAT MATRICES FOR EACH MEDIAN STATION K AND FOURIER MODE MN
** THESE MATRICES ARE COMPUTED AND SAVED BECAUSE THEY DO NOT
** CHANGE DURING EITHER THE ITERATION PROCEDURE OR THE LOAD INCRE-
** MENT PROCEDURE - AS THEY ARE A FUNCTION OF THE SHELL'S INITIAL
** GEOMETRY AND STIFFNESS.
**
COMMON /IBL4/ KMAX,KL
COMMON /BL1/ A(4,4),BEE(4,4),C(4,4)
COMMON /BL4/ P(4,4,200),ZF1M(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
1  ZF4M(4,4,10)
COMMON /BL34/ DEE(4,4,200),DST(4,4,200)
DIMENSION TM(4,4),IPIVE(4),INDEX(4,2),X2(4)
**
IKL=K+KMAX*(MN-1)
KL=IKL-1

```



```

2 1 1 I=1,4
    1 J=1,4
    SUM=0.
    DO 2 L=1,4
        SUM=SUM+C(I,L)*P(L,J,KLI)
    TM(I,J)=BEE(I,J)-SUM
    1 CALL MATINV(TM,4,X2,0,DETERM,IPIVOT,INDEX,4,ISCALE)
    DO 5 I=1,4
        DO 5 J=1,4
            SUMA=0.
            SUMC=0.
            DO 6 L=1,4
                SUMA=SUMA+TM(I,L)*A(L,J)
                SUMC=SUMC+TM(I,L)*C(L,J)
            6 P(I,J,IKL)=SUMA
            DEE(I,J,IKL)=TM(I,J)
            DST(I,J,IKL)=SUMC
        5 RETURN
    END

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18360

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[illegible]

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19140
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19180
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19300

```

DC 1 MM=NNS,MNMAXO
NM=N(N(MM))
NTEST=IABS(NMN-NMM)
DO 2 MMFT=1,MNMAX
IF(NTEST.EQ.N(MMFT)) GO TO 10
CONTINUE
2 IF(ICORFL.EQ.1) GO TO 1
NMMAX=MNMAX+1
N(MMFT)=NTEST
MMFT=MNMAX
IF(MNMAX.EQ.MAXM) ICORFL=1
10 IF(NMN-NMM) 11,1,12
11 LOCD=MAXD(MMFT)+1
MAXD(MMFT)=LOCD
12 LOCD,MMFT)=MM
JD(LOCD,MMFT)=MN
GO TO 1
LOCD=MAXD(MMFT)+1
MAXD(MMFT)=LOCD
11 LOCD,MMFT)=MN
JD(LOCD,MMFT)=MM
CONTINUE
1 DO 301 MN=1,MNMAXO
NNS=MN
N(MN)=N
IF(MNINIT.GT.MN) NNS=MNINIT
DO 301 MM=NNS,MNMAXO
NM=N(N(MM))
NTEST=MN+NM
DO 302 MMFT=1,MNMAX
IF(NTEST.EQ.N(MMFT)) GO TO 310
CONTINUE
302 IF(ICORFL.EQ.1) GO TO 301
IF(MNMAX.GE.MAXM) GO TO 301
NMMAX=MNMAX+1
N(MMFT)=NTEST
MMFT=MNMAX
IF(MNMAX.GE.MAXM) ICORFL=1
310 IF(NMN.EQ.NMM) GO TO 360
LOCS=MAXS(MMFT)+1
MAXS(MMFT)=LOCS
IS(LOCS,MMFT)=MN
JS(LOCS,MMFT)=MM
GO TO 301
360 IF(NN.EQ.O) GO TO 301
MAXSY(MMFT)=1
IJS(MMFT)=MN
301 CONTINUE

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19310
19320
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```

MNINIT=MNMAXO+1
IF(ICORFL.GT.0) IPASS=IPASS+1
IF(IPASS.LT.2.AND.MNINIT.LE.MNMAX) CALL PMATRIX
RETURN
END

```

19360
19370
19380
19390
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19690
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SUBROUTINE POLE(K)
C** THIS SUBROUTINE PRINTS THE SOLUTION AT AN INITIAL AND A FINAL
C** POLE.
C**
C** IMPLICIT LOGICAL*1 ($)
C** REAL NU,MT,MX,MTH,MXT,MTS,KX,KT,KXT,LAM,LAM2,MASS
C** COMMON /IBL2/ N(13),MNINIT
C** COMMON /IBL3/ M0,M1,M2,M3
C** COMMON /IBL4/ KMAX,KL
C** COMMON /IBL5/ IBCFNL,IBCFNL
C** COMMON /IBL7/ MNMAXC,MAYC(10),MAXS(10),MAXSY(10),IS(10,10),
1 JS(10,10),ID(10,10),JD(10,10),IJS(10)
C** COMMON /IBL8/ LSTEP,ITR
C** COMMON /IBL10/ IFREC,NTHMAX
C** COMMON /IBL12/ KMAX1,KMAX2,NCONV
C** COMMON /BL4/ P(4,4,200),ZF1N(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
1 ZF4M(4,4,10)
C** COMMON /BL5/ MT(10),DT(10),DMT(10)
C** COMMON /BL6/ SCE,ALCAD
C** COMMON /BL7/ OI,SI
C** COMMON /BL8/ P(200),GAN(200),OMT(200)
C** COMMON /BL10/ PHIX(10),PHIT(10),PHI(10)
C** COMMON /BL11/ QMXI(200),PHEE,T0,T2
C** COMMON /BL12/ TDLI,TDCL
C** COMMON /BL14/ LAM2,LSD18,LSD1N
C** COMMON /BL15/ NU,U(10),V(10),W1(10),W2(10),W3(10),U3(10),
1 V3(10),W3(10)
C** COMMON /BL17/ DEL
C** COMMON /BL19/ TH(36)
C** COMMON /BL20/ DECMX(200)
C** COMMON /BL27/ EX3(10),ST3(10),BXT3(10),BE3(10)
C** COMMON /BL31/ CELSQ,EXT1(10)
C** COMMON /BL32/ TKN,ELAST,CHAR,SIGO
C** COMMON /BL100/ TEE0,$DYNMC
C** COMMON /BL101/ DELSQD
C** COMMON /BL102/ DELCAD
C** COMMON /BL103/ MASS(200)
C** COMMON /BL104/ Z(4,220),ZDOT(4,220),X(4,200),ZO(4,220),Z2(4,220),
1 Z3(4,220)
C** COMMON /BL110/ TX(10),TXT(10F,MX(10),MTH(10),MXT(10),

```



```

1  COMMON /BL11/  AEZ,ABZC,ABZN,ABZ3,DD2
C**      *
CALL  BC8(K,BS,DB,DS,DC)
IF(K.EQ.KMAX) GO TO 301
DO 202 MN=1,MNMAXD
  U1(MN)=U2(MN)
  V1(MN)=V2(MN)
  W1(MN)=W2(MN)
  I3=3+(MN-1)*KMAX2
  I2=I3-1
  U2(MN)=Z(1,I3)
  V2(MN)=Z(2,I3)
  W2(MN)=Z(3,I3)
  PHIX(MN)=0.0
  PHIT(MN)=0.0
  PHI(MN)=0.0
  MX(MN)=Z(4,I2)*ABZ3
  MTH(MN)=0.0
  MXT(MN)=0.0
  QS(MN)=0.0
  TX(MN)=0.0
  TTH(MN)=0.0
  TTX(MN)=0.0
  IF(M1.EQ.0) GO TO 203
  CALL INLPOL
  PHIX(M1)=PFEE*ABZO
  PHIT(M1)=-PHEE*AEZO
  QS(M1)=0.0
  CONTINUE
  IF(M2.EQ.0) GO TO 204
  TX(M2)=T0*ABZ
  TTH(M2)=T0*ABZ
  MTH(M2)=MX(M2)
  IF(M2.EQ.0) GO TO 205
  TX(M2)=T2*ABZ
  TTH(M2)=-T2*ABZ
  MTH(M2)=-T2*ABZ
  MXT(M2)=-MX(M2)
  MXT(M2)=MTH(M2)
  GO TO 205
203  IF(M3.EQ.0) GO TO 206
  I3=3+(M0-1)*KMAX2
  I4=I3+1
  CALL TLOAD(1)
  TX(M0)=BS*SI*((2.*Z(1,I3)-.5*Z(1,I4))/DEL+OMXI(1)*Z(3,I3-1))*ABZ
  TTH(M0)=TX(M0)
1

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```

206 MTH(MO)=MX(MO)
    IF(M2.EQ.0) GO TO 205
    I3=3+(M2-1)*KMAX2
    I4=I3+1
    TX(M2)=8S*01*(2.*Z(1,I3)-.5*Z(1,I4))/DEL
    TX(M2) = TX(M2)*ABZ
    TTH(M2) = -TX(M2)
    TTX(M2) = -TX(M2)
    MTH(M2) = -MX(M2)
    MXT(M2) = -MX(M2)
    RETURN
205 CONTINUE
301 DO 302 MN=1,MNMAXO
    U1(MN)=U2(MN)
    V1(MN)=V2(MN)
    W1(MN)=W2(MN)
    PHIX(MN)=0.
    PHIT(MN)=0.
    PHI(MN)=0.
    IK=KMAX1+(MN-1)*KMAX2
    MX(MN)=Z(4,IK)*ABZ3
    MTH(MN)=0.
    MXT(MN)=0.
    QS(MN)=0.
    TX(MN)=0.
    TTH(MN)=0.
    TTX(MN)=0.
    IF(M1.EQ.0) GO TO 303
    CALL FNLPOL
    PHIX(M1)=PHEE*ABZO
    PHIT(M1)= PHEE*ABZO
    QS(M1)=0.
    CONTINUE
    IF(MO.EQ.0) GO TO 304
    TX(MO) = TO*ABZ
    TTH(MO) = T)*ABZ
    MTH(MO) = MX(MO)
    IF(M2.EQ.0) GO TO 305
    TX(M2) = T2*ABZ
    TTH(M2) = -T2*ABZ
    TTX(M2) = -T2*ABZ
    MTH(M2) = -MX(M2)
    MXT(M2) = MX(M2)
    GO TO 305
303 IF(MO.EQ.0) GO TO 306
    IKM=KMAX+(MO-1)*KMAX2
    IM1=IKM-1
    CALL TLOAD(KMAX)

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TX(M0)=BS*S1*((-2.*Z(1,IKM)+.5*Z(1,IM1))/DEL+OMXI(KMAX)*Z(3,IKM+1)
) *ABZ-TT(M0)*ABZ*ALOAD
1 TTH(M0)=TX(M0)
MTH(M0)=MX(M0)
IF(M2.EQ.0) GO TO 305
IKM=KMAX+(M2-1)*KMAX2
IM1=IKM-1
TX(M2)=BS*DI*((-2.*Z(1,IKM)+.5*Z(1,IM1))/DEL
) *ABZ
1 TTH(M2)=TX(M2)
MTH(M2)=MX(M2)
NXT(M2)=TX(M2)
MXT(M2)=MX(M2)
RETURN
305 END

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21180

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SUBROUTINE INLPOL
C THIS SUBROUTINE COMPUTES THE NON-LINEAR TERMS BETA-S,
C -SUB THETA, -SUB S-THETA, AETA-SUB S-S AND -SUB THETA-S AT AN
C INITIAL PCLF.
C
C COMMON /IBL1/ MNMAX
C COMMON /IBL3/ M0,M1,M2,M3
C COMMON /IBL12/ KMAX1,KMAX2,NCONV
C COMMON /IBL13/ ITRMAX,LSMAX
C COMMON /BL5/ TT(10),ENT(10),DT(10),DMT(10)
C COMMON /BL6/ SOE,OSE,ALOAD
C COMMON /BL7/ DI,SI
C COMMON /BL11/ OMXI(200),PREE,TO,T2
C COMMON /BL17/ DEL
C COMMON /BL29/ BXT1(10),BXT1(10),BE1(10),BX2(10),BT2(10),
1 BXT2(10),SET(10)
1 EXX1(10),ETX1(10),ETX1(10),EX1(10),ET1(10),EXX2(10),
ETT2(10),ETX2(10),EX2(10),ET2(10)
1 CCMMON /BL30/ EXX1(10),EXX1(10),EXX1(10),EXX1(10),EXX1(10),
CCMMON /BL31/ DELSO,EX1(10)
1 CCMMON /BL104/ Z(4,220),Z(4,220),Z(4,220),Z(4,220),
Z(4,220)
C
C DC 1 MN=1, MNMAX
BXT1(MN)=0.
BT1(MN)=0.
BXT1(MN)=0.
BE1(MN)=0.
EX1(MN)=0.
ET1(MN)=0.
ETX1(MN)=0.

```



```

1 EXXI(MN)=0.
  IF(M1.EQ.0) RETURN
  I2=2+(M1-1)*KMAX2
  I3=I2+1
  I4=I3+1
  I5=Z(3,I2)-2.*Z(3,I3)+.5*Z(3,I4))/DEL+OMXI(1)*Z(1,I2)
  PHEE=.5*PHEE**2
  IF(I1*TRMAX.EQ.1) BET=0.
  T2=0.
  IF(M2.EQ.0) GO TO 2
  CALL BC9(1,B,DB,D,DD)
  I2=2+(M2-1)*KMAX2
  I3=I2+1
  I4=I3+1
  I5=Z(3,I2)-2.*Z(3,I3)+.5*Z(3,I4))/DEL+.5*SOE*BET)
  Q1=-.5*PHEE**T2
  BX1(M2)=BET
  BT1(M2)=-BET
  BXT1(M2)=-BET
  ETX1(M1)=Q1
  IF(M3.EQ.0) GO TO 2
  EXXI(M3)=Q1
  ETX1(M3)=-Q1
  T1=0.
  IF(M0.EQ.0) GO TO 3
  BX1(M0)=BET
  BT1(M0)=-BET
  CALL BC8(1,B,DB,D,DD)
  CALL TLOAD(1)
  I2=2+(M0-1)*KMAX2
  I3=I2+1
  I4=I3+1
  I5=Z(3,I2)-2.*Z(3,I3)+.5*Z(3,I4))/DEL+OMXI(1)*Z(3,I2)
  I6=Z(3,I3)-2.*Z(3,I4)+.5*Z(3,I5))/DEL+OMXI(1)*Z(3,I2)
  I7=Z(3,I4)-2.*Z(3,I5)+.5*Z(3,I6))/DEL+OMXI(1)*Z(3,I2)
  EXXI(M1)=PHEE*(I0+.5*T2)
  RETURN
END

```

```

SUBROUTINE ENLPOL
C *** THIS SUBROUTINE COMPUTES THE NON-LINEAR TERMS BETA-SUB S, AT A ***
C *** -SUB THETA, -SUB S-THETA, AETA-SUB S-S, AND -SUB THETA-S, AT A ***
C *** FINAL POLE. ***
C *** COMMON /IBL1/ MNMAX
C *** COMMON /IBL3/ M0,M1,M2,M3
C *** COMMON /IBL4/ KMAX,KL

```



```

COMMON /IBL12/ KMAX1,KMAX2,NCCNV
COMMON /IBL13/ ITRMAX,LSIAX
COMMON /BL5/ TT(10),EMT(10),DT(10),DMT(10)
COMMON /BL6/ SOE,CSE,ALC10
COMMON /BL7/ CI,SI
COMMON /BL11/ OMXI(200),PHEE,T0,T2
COMMON /BL17/ DEL
COMMON /BL27/ BX3(10),BT3(10),BE3(10)
COMMON /BL28/ EXX3(10),ET3(10),EXT3(10)
COMMON /BL104/ Z(4,220),Z0(4,200),X(4,200),Z2(4,220),
1 Z3(4,220)
C*****
DO 1 MN=1,MNMAX
BX3(MN)=0.
BT3(MN)=0.
EXX3(MN)=0.
ET3(MN)=0.
EXT3(MN)=0.
EXX3(MN)=0.
CALL BOB(KMAX,B,DB,D,DB)
IF(M1.EQ.0) RETURN
KM=KMAX1+(M1-1)*KMAX2
KM1=KM-1
KM2=KM-2
PHEE=-(1.5*Z(3,KM)-2.*Z(3,KM1)+.5*Z(3,KM2))/DEL+OMXI(KMAX)*Z(1,KM)
BET=.5*PHEE**2
IF(ITRMAX.EQ.1) BET=0.
T2=0.
IF(M2.EQ.0) GO TO 2
KM=KMAX1+(M2-1)*KMAX2
KM1=KM-1
KM2=KM-2
T2=B+Q1*(1.5*Z(1,KM)-2.*Z(1,KM1)+.5*Z(1,KM2))/DEL+.5*SOE*BET
Q1=.5*PHEE**T2
BX3(M2)=-BET
BT3(M2)=BET
EXT3(M1)=Q1
EXX3(M3)=Q1
EXT3(M3)=-Q1
TJ=0.
IF(M0.EQ.0) GO TO 3
CALL TLOAD(KMAX)
KM=KMAX1+(M0-1)*KMAX2
KM1=KM-1
2

```


22130
22140
22150
22160
22170
22180
22190
22200

```

KM2=KM-2
BX3(MO)=BET
BT3(MO)=BET
TC=B*SI*(1.5*Z(1,KM1)+.5*Z(1,KM2))/DEL+OMXI(KMAX)*
1 Z(3,KM1)+.5*SOE*BET)-TT(PJ)*ALOAD
3 EXX3(M1)=PHEE*(TC+.5*T2)
RETURN
END

```

22210
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```

C** SUBROUTINE PHIBET(K)
C**
C** THIS SUBROUTINE CALCULATES THE PHI'S AND CARRIES OUT THE
C** MULTIPLYING AND SUMMATION PROCEDURE FOR COMPUTING THE BETA
C** NON-LINEAR TERMS FOR A GIVEN PERIODICAL STATION K. THE ARRAYS
C** IS, JS, ID, JS, IJS, MAXD, MAXSY ARE PREPARED IN SUB-
C** ROUTINE MODES AND USED HERE.
C**
C** COMMON /IBL1/ MNMAX
C** COMMON /IBL2/ N(10), MNINIT
C** COMMON /IBL4/ KMAX, KL
C** COMMON /IBL7/ J(10,10), MAXS(10), MAXSY(10), IS(10,10),
1 JS(10,10), ID(10,10), JD(10,10), IJS(10,10)
C** COMMON /IBL12/ KMAX1, KM, X2, NCONV
C** COMMON /IBL13/ ITRMAX, L, MAX
C** COMMON /IBL6/ SQ, QSE, AL, AD
C** COMMON /BL8/ R(200), GA(200), OMT(200)
C** COMMON /BL10/ PHIX(10), PHIT(10), PHI(10)
C** COMMON /BL11/ OMXI(200), PHEE, TO, T2
C** COMMON /BL12/ TDLI, TCEL
C** COMMON /BL15/ NU, UI(10), V1(10), V2(10), U2(10), W2(10), U3(10),
1 V3(10), W3(10)
C** COMMON /BL27/ BX3(10), BXT3(10), BE3(10)
C** COMMON /BL104/ Z(4,220), ZDCT(4,220), X(4,220), ZC(4,220),
1 Z3(4,220), Z3(4,220)
C**
C** OX=OMXI(K)
C** CT=CMT(K)
C** RRA=1./R(K)
C** GA=GAM(K)
C** KP2=K+2
C** DO 1 M=1, MNMAXC
C** EN=N(M)
C** IK=KP2+(M-1)*KMAX2
C** U3(M)=Z(1,IK)
C** V3(M)=Z(2,IK)
C** W3(M)=Z(3,IK)
C** PHIX(M)=-TDLI*(W3(M)-X1(Y))+OX*U2(M)

```



```

1 PHIT(M)=EN*W2(M)*RRA+V2(M)*QT
  IF(ITRMAX.EQ.1) RETURN
  DO 9 M=1,MNMAX
    SMO=0.
    SMT=0.
    SMR=0.
    SMF=0.
    IF(N(M).EQ.0) GO TO 20
    MAXL=MAXS(M)
    IF(MAXL.EQ.0) GO TO 2
    DO 3 L=1,MAXL
      I=IS(L,M)
      J=JS(L,M)
      SMO=SMO+PHIX(I)*PHIX(J)
      SMT=SMT-PHIT(I)*PHIT(J)
      SMR=SMR+PHIX(I)*PHIT(J)+PHIX(J)*PHIT(I)
      SMF=SMF-PHI(I)*PHI(J)
      MAXL=MAXD(M)
      IF(MAXL.EQ.0) GO TO 4
      DO 5 L=1,MAXL
        I=ID(L,M)
        J=JD(L,M)
        SMC=SMO+PHIX(I)*PHIX(J)
        SMT=SMT+PHIT(I)*PHIT(J)
        SMR=SMR+PHIX(I)*PHIT(J)+PHIX(J)*PHIT(I)
        SMF=SMF+PHI(I)*PHI(J)
        IF(MAXSY(M).EQ.0) GC TO 10
        I=IJS(M)
        J=JCS(M)
        SMC=SMO+PHIX(I)*2/2.
        SMT=SMT-PHIT(I)*2/2.
        SMR=(SMR+PHIX(I)*PHIT(I))
        SMF=SMF-PHI(I)*2/2.
        GO TO 10
      DO 21 L=1,MNMAXO
        SMC=SMO+PHIX(L)*2
        SMT=SMT+PHIT(L)*2
        SMR=SMR+PHIX(L)*2
        SMF=SMF+PHI(L)*2
        IF(M.GT.MNMAXO) GO TO 11
        SMO=SMO+PHIX(M)*2
        BX3(M)=SMO*.5
        BT3(M)=SMT*.5
        BXT3(M)=SMF*.5
        GO TO 5
      DO 10 L=1,5
        BX3(M)=SMO
        BT3(M)=SMT
        BXT3(M)=SMR*.5

```

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 22990
 23000
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23090
23100

BE3(M)=SMF
9 CONTINUE
RETURN
END

23110
23120
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23500
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23520

```

SUBROUTINE TEAETA(K)
C THIS SUBROUTINE CALCULATES THE INPLANE FORCES AND CARRIES OUT
C THE MULTIPLYING AND SUMMATION PROCEDURE FOR COMPUTING THE AETA
C NON-LINEAR TERMS FOR A GIVEN PERIODICAL STATION K. THE ARRAYS
C IS, JS, ID, JS, IJS, MAXS, MAXC, MAXSY PREPARED IN SUBROUTINE
C MODES ARE USED HERE.
C
REAL NU, MT
COMMON /IBL1/ MNMAX
COMMON /IBL2/ N(10), MNMAXC, MAXC(10), MAXS(10), MAXSY(10), IS(10,10),
COMMON /IBL7/ JS(10,10), ID(10,10), JD(10,10), IJS(10,10),
1 LSTEP, ITR, CMAX
COMMON /IBL8/ LSTEPMAX, LCMAX
COMMON /IBL13/ IT(10), NI(10), DT(10), DMT(10)
COMMON /BL5/ SOE, OSE, ALCOA
COMMON /BL7/ SI, S1
COMMON /BL8/ R(200), CMT(200)
COMMON /BL10/ PHIX(10), PHIT(10), PHI(10)
COMMON /BL11/ QMXI(200), PHEE, T0, T2
COMMON /BL12/ TDLI, TDEL
COMMON /BL15/ NU, UI(10), V1(10), V2(10), U2(10), W2(10), U3(10),
1 V3(10), W3(10)
COMMON /BL27/ BX3(10), BXT3(10), BE3(10)
COMMON /BL28/ EXX3(10), ETX3(10), EX3(10), ET3(10)
DIMENSION TX(10), TTH(10), TTX(10)
C
PRA=1./R(K)
GA=GAM(K)
CX=CMXI(K)
CT=QMT(K)
CALL BCB(K, BS, DB, DS, DD)
DO 1 M=1, MNMAXG
EN=N(M)
CALL TLOAD(K)
TTS=TT(M)*ALOAD
EX=(U3(M)-UI(M))*TDLI+CX*J2(M)+OSE*(BX3(M)+BE3(M))
ET=EN*V2(M)*RRA+GA*U2(M)+OT*W2(M)+OSE*(BT3(M)+BE3(M))
EXT=.5*(TDLI*(V3(M)-V1(M))-EN*U2(M)*RRA-GA*V2(M))+OSE*BXT3(M)
TX(M)=BS*(CX+NU*ET)-TT
TTH(M)=BS*(ET+NU*EX)-TT

```


1	IXT(M)=BS*DI*EXT	23530
	DO 9 M=1,MNMAX	23540
	SMF=0.	23550
	SMV=0.	23560
	SME=0.	23570
	SMN=0.	23580
	SMT=0.	23590
	IF(N(M).EQ.0) GO TO 20	23600
	MAXL=MAX(XS(M)	23610
	IF(MAXL.EQ.0) GO TO 2	23620
	DO 3 L=1,MAXL	23630
	I=IS(L,M)	23640
	J=JS(L,M)	23650
	SMF=SMF+TX(I)*PHIX(J)+TTH(J)*PHIX(I)	23660
	SMS=SMS+TTH(I)*PHIT(J)+TTH(J)*PHIT(I)	23670
	SMV=SMV-PHIT(I)*TXI(J)-PHIT(J)*TXI(I)	23680
	SME=SME+PHIX(I)*TXI(J)+PHIX(J)*TXI(I)	23690
	SMN=SMN+TX(I)*PHI(J)+TX(J)*PHI(I)	23700
	SMT=SMT+TTH(I)*PHI(J)+TTH(J)*PHI(I)	23710
	MAXL=MAX(XD(M)	23720
3	IF(MAXL.EQ.0) GO TO 4	23730
2	DO 5 L=1,MAXL	23740
	I=ID(L,M)	23750
	J=JD(L,M)	23760
	SMF=SMF+TX(I)*PHIX(J)+TTH(J)*PHIX(I)	23770
	SMS=SMS-TTH(I)*PHIT(J)+TTH(J)*PHIT(I)	23780
	SMV=SMV-PHIT(I)*TXI(J)+PHIT(J)*TXI(I)	23790
	SME=SME-PHIX(I)*TXI(J)+PHIX(J)*TXI(I)	23800
	SMN=SMN-TX(I)*PHI(J)+TX(J)*PHI(I)	23810
	SMT=SMT-TTH(I)*PHI(J)+TTH(J)*PHI(I)	23820
5	IF(MAXSY(M).EQ.0) GO TO 10	23830
4	I=IJS(M)	23840
	SMF=SMF+TX(I)*PHIX(I)	23850
	SMS=SMS+TTH(I)*PHIT(I)	23860
	SMV=SMV-PHIT(I)*TXI(I)	23870
	SME=SMF+PHIX(I)*TXI(I)	23880
	SMN=SMN+TX(I)*PHI(I)	23890
	SMT=SMT+TTH(I)*PHI(I)	23900
	GO TO 10	23910
20	GO 21 L=1,MNMAXO	23920
	SMF=SMF+TX(L)*PHIX(L)	23930
21	SMV=SMV+PHIT(L)*TXI(L)	23940
	IF(M.GT.MNMAXO) GO TO 10	23950
	SMF=SMF+TX(M)*PHIX(M)	23960
10	EXX3(M)=SMF*.5	23970
	ETT3(M)=SMS*.5	23980
	ETX3(M)=SMV*.5	23990
		24000


```

EXT3(M)=SME*.5
EX3(M)=SMN*.5
ET3(M)=SMT*.5
CCNTINUE
9 DO 30 M=1,MNMAXO
  U1(M)=U2(M)
  V1(M)=V2(M)
  W1(M)=W2(M)
  U2(M)=U3(M)
  V2(M)=V3(M)
  W2(M)=W3(M)
30 RETURN
END

```

24010
24020
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24090
24100
24110
24120
24130

```

SUBROUTINE UPDATE
C *** THIS SUBROUTINE UPDATES THE STORAGE LOCATIONS OF THE BETA'S AND
C *** ETAS. IT IS CALLED IN SUBROUTINE XANDZ AFTER A MERIDIAN
C *** STATION CHANGE. ***
C ***
COMMON /IRL1/ MNMAX
COMMON /BL27/ EXX3(10),ETX3(10),EX3(10),BT3(10)
COMMON /BL28/ EXX1(10),ETX1(10),BX2(10),BT2(10),
COMMON /BL29/ EXX2(10),ETX2(10)
1 COMMON /BL30/ EXX1(10),ETX1(10),EX1(10),ET1(10),EXX2(10),
1 ETX2(10),ETX2(10),EX2(10),ET2(10)
C *** CELSO, XTI(10) ***
COMMON /BL31/
C ***
CO 1 M=1,MNMAX
BX1(M)=BX2(M)
BT1(M)=BT2(M)
BX11(M)=BX12(M)
BX1(M)=BX2(M)
BX2(M)=BX3(M)
BT2(M)=BT3(M)
BX2(M)=BX3(M)
EXX1(M)=EXX2(M)
ETX1(M)=ETX2(M)
ETX1(M)=ETX2(M)
EXX1(M)=EXX2(M)
ETX1(M)=ETX2(M)
EXX2(M)=EXX3(M)
ETX2(M)=ETX3(M)
ETX2(M)=ETX3(M)

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24430
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24450
24460


```

EXT2(M)=EXT3(M)
EXT2(M)=EXT3(M)
1 RETURN
END

```

```

24470
24480
24490
24500
24510

```

```

SUBROUTINE OUTPUT(IMODE)
** ** ** ** **
** THIS SUBROUTINE PREPARES THE PRINTOUT MATERIAL. EVERY IPRINT **
** CONVERGED SOLUTION IS PRINTED. THE FOURTH COEFFICIENTS OF THE **
** INPLANE FORCES, MERIDIONAL TRANT, NSVERSE FORCE, CIRCUMFERENTIAL **
** BENDING MOMENT, TWISTING MOMENT AND ROTATIONS CAN BE COMPUTED **
** AND PRINTED WITH THE SOLUTIONS FOR THE FOURIER COEFFICIENTS. THIS **
** OF THE THREE-DIAL IS CONVERSION FROM DIMENSIONLESS FORM TO DIMEN- **
** OUTPUT MATERIAL HERE. I, ETC. THIS SUBROUTINE PRINT ONLY AT STATIONS **
** SIONAL FORM HERE. I, ETC. THIS SUBROUTINE PRINT ONLY AT STATIONS **
** I, IFREQ+1, PROCESS RESULTS AND ROTATIONS AT THE INPUT DATA. **
** SUMMATIONS, DISPLACEMENTS AND ROTATIONS AT THE INPUT DATA. **
** AROUND THE CIRCUMFERENCE PREPARED HERE, IF REQ'D **
** DATA TO BE PLOTTED IS PREPARED HERE, IF REQ'D **
** ** ** ** **
** IMPLICIT LOGICAL*1 (S) **
** REAL NU,MT,MX,MTH,MXI,MTS,KX,KT,KXT,LAM,LAM2,MASS **
** COMMON /IBL2/ N(10),M1,M2,M3 **
** COMMON /IBL3/ M1,M2,M3 **
** COMMON /IBL4/ KMAX,KL **
** COMMON /IBL5/ IBCINL,IBCFNL **
** COMMON /IBL7/ MNMAXD,MAXD(10),ID(10,10),JD(10,10),IJS(10) **
** ** ** ** **
1 COMMON /IBL8/ LSTEP,ITR **
COMMON /IBL10/ IFREQ,NTHMAX **
COMMON /IBL12/ KMAX1,KMAX2,NCONV **
COMMON /IBL13/ ITRMAX,LSMAX **
COMMON /IBL4/ P(4,4,200),ZF1M(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10), **
ZF4M(4,4,10) **
1 COMMON /BL5/ ZF4M(4,4,10) **
COMMON /BL6/ DT(10),DMT(10) **
COMMON /BL7/ SOE,DOSE,ALOAD **
COMMON /BL7/ DI,SI **
COMMON /BL8/ R(200),GMT(200) **
COMMON /BL10/ PHIX(10),PHI(10) **
COMMON /BL11/ CMXI(200),PHEE,T0,T2 **
COMMON /BL12/ TDLI,TOEL **
COMMON /BL14/ LAM2,LSCL8,LSDIN **
COMMON /BL15/ NU,U1(10),V1(10),W1(10),V2(10),U2(10),W2(10),U3(10), **
V3(10),W3(10) **
1 COMMON /BL17/ DEL

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24690
24700
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24800
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24900
24910
24920

```



```

1 ICHCK2=IABS(IU)+IABS(IMSTH)+IABS(IPHIS)+IABS(IPHIT)
1 IF(NTHMAX.EQ.0) GO TO 991
IF($VIRE$) GO TO 991
DO 21 NTH=1,NTHMAX
DO 1 MN=1,MNMAXO
I1=1+(MN-1)*KMAX2
I2=I1+1
U1(MN)=Z(1,I1)
U2(MN)=Z(1,I2)
V1(MN)=Z(2,I1)
V2(MN)=Z(2,I2)
W1(MN)=Z(3,I1)
W2(MN)=Z(3,I2)
THET=TH(NTH)
WRITE(6,I16) THET
DO 121 K=1,KMAX
K1=K+1
CALL BD9(K,BS,DB,DS,DD)
IF(K.EQ.1.AND.IBCINL.LT.0) CALL POLE(K)
IF(K.EQ.1.AND.IBCINL.LT.0) GO TO 999
IF(K.EQ.KMAX.AND.IBCFNL.LT.0) CALL POLE(K)
IF(K.EQ.KMAX.AND.IBCFNL.LT.0) GO TO 999
CALL PHIBET(K)
DEX=DEOMX(K)
BRA=1./R(K)
OX=OMXI(K)
OT=OMT(K)
GA=GAM(K)
COXT=OX-OT
GDO=GADOCXT
DO2D=DC2*DS
DO 3 MN=1,MNMAXO
ENR=EN(MN)
ENR=EN*RA
CALL TLOAD(K)
TTS=TT(MN)*ALOAD
EX=(U3(MN)-U1(MN))*TDLI+OX*W2(MN)+ENL*QSE*(BX3(MN)+BE3(MN))
ET=ENR*V2(MN)+GA*U2(MN)+OT*W2(MN)+ENL*QSE*(BT3(MN)+BE3(MN))
EXT=.5*(V3(MN)-V1(MN))*TDLI-ENR*U2(MN)-GA*V2(MN)+ENL*SOE*BXT3(MN)
1) KT=ENR*PHIT(MN)+GA*PHIX(MN)
KXT=.5*(ENR*(-PHIX(MN)-GA*W2(MN))+W3(MN)-W1(MN))*TDLI+GDO*V2(MN)
1) OT*(V3(MN)-V1(MN))*TDLI-GA*PHIT(MN)-DCXT*PHI(MN)
TX(MN)=BS*(EX+NU*ET)-TTS
TTH(MN)=BS*(ET+NU*EX)-TTS
TXT(MN)=BS*D1*EXT

```



```

MK1=K1+(MN-1)*KMAX2
MX(MN)=Z(4,MK1)
MTH(MN)=NU*MX(MN)+DD2D*KT-D1*NT(MN)*ALOAD
MXT(MN)=DS*D1*KXT
MK11=MK1+1
MKK1=MK1-1
1  QS(MN)=SIGO*TKN*LAM2*(GA*MX(MN)+(Z(4,MK11)-Z(4,MK1))*TDLI
    +ENR*MX(MN)-GA*MTH(MN))
    MX(MN)=MX(MN)*ABZ3
    MTH(MN)=MTH(MN)*ABZ3
    MXT(MN)=MXT(MN)*ABZ3
    TX(MN)=TX(MN)*ABZ
    TTH(MN)=TTH(MN)*ABZ
    TXT(MN)=TXT(MN)*ABZ
    PHIX(MN)=PHIX(MN)*ABZO
    PHIT(MN)=PHIT(MN)*ABZO
    PHI(MN)=PHI(MN)*ABZC
    U1(MN)=U2(MN)
    U2(MN)=U3(MN)
    V1(MN)=V2(MN)
    V2(MN)=V3(MN)
    W1(MN)=W2(MN)
    W2(MN)=W3(MN)
    FK=K-1
    IFREQ=IFREQ
    KTST=(K-1)/IFREQ
    FKST=KTST
    FKTEST=FK/IFREQ-FKTST
    IF(K.EC.1-GR.K.EC.KMAX) GO TO 999
    IF(FKTEST.NE.0.) GC TC 2
999 X(1,K)=0.
    X(2,K)=0.
    X(3,K)=0.
    X(4,K)=0.
    PTF(K)=0.
    PF(K)=0.
    AMX=0.
    AMTH=0.
    AMXTH=0.
    ANX=0.
    ANTH=0.
    ANXTH=0.
    AQS=0.
    DO 72 MN=1,MNMAXO
    EA=N(MN)
    EC=EN*THET
    SN=SIN(EC)
    CS=COS(EC)

```



```

658 DO 659 I=1,4
659 X(I,K)=0.
660 CONTINUE
660 IF ($PLOTS.AND..NOT.$MODAL.AND.((ICHECK1.GT.0).OR.(ICHECK2.GT.0)))
1 CALL PLOT2(NTH)
21 CONTINUE
991 IF(IMODE.LE.0) RETURN
DO 534 MN=1,MNMAXO
IF(.NOT.$VIBES) WRITE(6,749) N(MN)
DO 521 MM=1,MNMAXG
I1=1+(MM-1)*KMAX2
I2=I1+1
U1(MM)=Z(1,I1)
U2(MM)=Z(1,I2)
V1(MM)=Z(2,I1)
V2(MM)=Z(2,I2)
W1(MM)=Z(3,I1)
W2(MM)=Z(3,I2)
521 CONTINUE
DO 445 K=1, KMAX
K1=K+1
CALL BD3(K,BS,DB,DS,DD)
IF(K.EQ.1.AND.IBCINL.LT.0) CALL POLE(K)
IF(K.EQ.KMAX.AND.IBCFNL.LT.0) CALL POLE(K)
TXZ=TX(MN)
TTHZ=TTH(MN)
THTZ=TH(MN)
AMXZ=MX(MN)
AMTHZ=MTH(MN)
AMXTZ=MX(MN)
CSZ=QS(MN)
X(1,K)=PHIX(MN)
X(2,K)=PHIT(MN)
X(3,K)=PHI(MN)
IF(K.EQ.1.AND.IBCINL.LT.0) GO TO 583
IF(K.EQ.KMAX.AND.IBCFNL.LT.0) GO TO 583
CALL PHIBET(K)
DEX=DECMX(K)
RRA=1./R(K)
CX=CMXI(K)
CT=QMT(K)
GA=GAM(K)
COXT=OX-CT
GDOO=GA#DCXT
CO2C=CO2#DS
ENR=EN-RRR
CALL TLOAD(K)

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```

TTS=TT(MN)*ALOAD
EX=(U3(MN)-U1(MN))*TCL I+OX*W2(MN)+ENL*OSE*(BX3(MN)+BE3(MN))
ET=ENR*V2(MN)+GA*U2(MN)+OT*W2(MN)+ENL*OSE*(BT3(MN)+BE3(MN))
EXT=.5*((V3(MN)-V1(MN))*TDL I-ENR*U2(MN)-GA*V2(MN)+ENL*SOE*BXT3(MN)
1)
KT=ENR*PHIT(MN)+GA*PHIX(MN)
KXT=.5*((ENR*(-PHIX(MN)-GA*W2(MN)+(W3(MN)-W1(MN))*TDL I)+GDO*V2(MN)
1) +OT*(V3(MN)-V1(MN))*TDL I-GA*PHIT(MN)-DCXT*PHI(MN))
TXZ=(BS*(EX+NU*ET)-TIS)*ABZ
TTHZ=(BS*(ET+NU*EX)-TIS)*ABZ
TXTZ=BS*DI*EXT*ABZ
MKI=KI+(MN-I)*KMAX2
AMXZ=Z(4,MKI)
AMTHZ=NU*AMXZ+DD2D*KT-DI*MT(MN)*ALOAD
AMXTZ=DS*DI*KXT
MKI1=MKI+1
MKK1=MKI-1
QSZ=SIGO*TKN*LAM2*(GA*AMXZ+(Z(4,MKK1)-Z(4,MKI))*TDL I+ENR*AMXTZ
1) -GA*AMTHZ)
AMXZ=AMXZ*ABZ3
AMTHZ=AMTHZ*ABZ3
AMXTZ=AMXTZ*ABZ3
X(1,K)=PHIX(MN)*ABZO
X(2,K)=PHIT(MN)*ABZC
X(3,K)=PHI(MN)*ABZO
CO 533 MZ=1,MN*MAXO
U1(MM)=U2(MM)
U2(MM)=U3(MM)
V1(MM)=V2(MM)
V2(MM)=V3(MM)
W1(MM)=W2(MM)
W2(MM)=W3(MM)
FK=K-1
IFREQ=IFREQ
KTST=(K-1)/IFREQ
FKTST=KTST
FKTEST=FK/IFREQ-FKTST
IF(K.EQ.1.CR.K.EC.KMAX) GO TO 583
IF(FKTEST.NE.O.) GO TO 445
CONTINUE
IF(K.EQ.1) WRITE(6,117)
IF((K.EQ.1.AND.IBCINL.LT.O).OR.(K.EQ.KMAX.AND.IBCFNL.LT.O))
1 GO TO 4444
GO TO 4445
4444 WRITE(6,1181) K,TXZ,TTHZ,TXTZ,AMXZ,AMTHZ,AMXTZ
GO TO 4446
4445 WRITE(6,118) K,TXZ,TTHZ,TXTZ,QSZ,AMXZ,AMTHZ,AMXTZ
4446 IF (.NOT.$PLOTS.CR..NOT.$MODAL.OR.(ICCHK1.EQ.O)) GO TO 445
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27750
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27800

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YNS(K)=TXZ
YNTH(K)=THZ
YNSTH(K)=TXTZ
YQS(K)=QSZ
YMS(K)=AMXZ
YMTH(K)=AMTHZ
YNSTH(K)=AMXTZ
445 CONTINUE
446 WRITE(6,217)
      DO 447 K=1,KMAX
      FK=K-1
      FIFREQ=IFREQ
      FKST=(K-1)/IFREQ
      FKTEST=FK/FIFREQ-FKTST
      IF(K.EQ.1.OR.K.EQ.KMAX) GO TO 593
      IF(FKTST.NE.0.) GO TO 447
      KZ=K+1+(MN-1)*KMAX2
      UP=Z(1,KZ)*ABZN
      VP=Z(2,KZ)*ABZN
      WP=Z(3,KZ)*ABZN
      WRITE(6,218) K,UP,VP,WP,X(1,K),X(2,K),X(3,K)
      IF (.NOT.$PLOTS.CR..NOT.$MODAL.OR.(ICHCK2.EQ.0)) GO TO 447
      YU(K)=UP
      YV(K)=VP
      YW(K)=WP
      YPHIS(K)=X(1,K)
      YPHIT(K)=X(2,K)
      YPHI(K)=X(3,K)
      447 CONTINUE
      IF ($PLOTS.AND.$MODAL.AND.((ICHCK1.GT.0).OR.(ICHCK2.GT.0)))
      1 CALL PLOT2(1)
534 CONTINUE
C *****
101 FORMAT('1.1',
101 LOAD FACTOR IS 'E11.4',
21 ITERATIONS'////)
116 FORMAT('0.1',
116 10 ROTATIONS FOLLOW FOR THETA ='E15.6'//)
117 FORMAT('1.1',
117 10 ROTATIONS FOLLOW FOR THETA ='E15.6'//)
118 FORMAT('1X,13.3X,7E16.4')
1181 FORMAT('1X,13.3X,3E16.4')
1181 FCNTH(K)=1.1,
1181 THE TIME IS 'F5
1.2.1 CR 'E9.3.1 SECCNS
3RATIONS'////)
217 FORMAT('1.1',
217 10 ROTATIONS FOLLOW FOR THETA ='E15.6'//)
      N THETA
      M THETA
      N STHETA
      M STHETA'//)
      NOT COMPUTED '3E16.4)
      STEP NUMBER IS '14.1' THE TIME IS 'F5
      THE SOLUTION CONVERGED IN '12.1' ITE
      PHI S
      PHI THETA
      PHI'//)
      W

```



```

218 FORMAT(1X,I3,3X,6E16.4)
749 FORMAT(11,40X,'MODAL OUTPUT FOR MODE N = ',I3,' FOLLOWS')
C*****
RETURN
END
28290
28300
28310
28320
28330

```

```

SUBROUTINE PLOT1(I)
C*****
C THIS SUBROUTINE CALLS PLOTTING ROUTINES FOR APPROPRIATE (USER
C SPECIFIED) INPUT QUANTITIES
C*****
IMPLICIT LOGICAL*1 ($)
COMMON /BL4/ KMAX,KL
COMMON /BLPLOT/
1 IRADII,IGAMMA,IOMEGS,IOMEGT,IDEOMS,IBSTIF,IDSTIF,
2 IBSTF,IBDSTF,IPR,IPS,IPT,ITT,IMT,IDTT,IMT,INS,
3 INTH,INSTH,IQS,IMS,IMTH,IMSTH,IU,IV,IM,IPHS,
4 IPHI,I$PHI,$PLOTS,$MODAL
COMMON /BLPLT1/ XRADII(100),YGAMMA(100),YOMEGS(100),YOMEGT(100),
1 YDECHS(100),YBSTIF(100),YDSTIF(100),YBBSIF(100),
2 YDSTF(100),YPR(100),YPS(100),YPT(100),YIT(100),
3 YMT(100),YDT(100),YPT(100),YNS(100),YNTH(100),
4 YNSTH(100),YQS(100),YMS(100),YMTH(100),YMSTH(100),
5 YU(100),YV(100),YW(100),YPHIS(100),YPHIT(100),
6 YPHI(100),XSTATN(100)
C*****
NGKMAX=-KMAX
IF (I-GT-1) GO TO 1
IF (IRADII.EQ.0) GO TO 2
WRITE (6,1000)
CALL PLOTIT(XSTATN,XRADII,NGKMAX,0)
WRITE (6,1001)
2 IF (IGAMMA.EQ.0) GO TO 4
WRITE (6,1000)
CALL PLOTIT(XSTATN,YGAMMA,NGKMAX,0)
WRITE (6,1002)
4 IF (IOMEGS.EQ.0) GO TO 5
WRITE (6,1000)
CALL PLOTIT(XSTATN,YOMEGS,NGKMAX,0)
WRITE (6,1003)
5 IF (IOMEGT.EQ.0) GO TO 6
WRITE (6,1000)
CALL PLOTIT(XSTATN,YCMEGT,NGKMAX,0)
WRITE (6,1004)
6 IF (IDEOMS.EQ.0) GO TO 7
WRITE (6,1000)
CALL PLOTIT(XSTATN,YDEOMS,NGKMAX,0)
WRITE (6,1005)
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28420
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1001 FORMAT ('0',T10,'RADIUS VS STATION')
1002 FORMAT ('0',T10,'GAMMA VS STATION')
1003 FORMAT ('0',T10,'OMEGA-THETA VS STATION')
1004 FORMAT ('0',T10,'DECEGAIN-SESS VS STATION')
1005 FORMAT ('0',T10,'3-STIFFNESS VS STATION')
1006 FORMAT ('0',T10,'DB-STIFFNESS VS STATION')
1007 FORMAT ('0',T10,'CORRIDOR-LOADING VS STATION')
1008 FORMAT ('0',T10,'INCIDENTAL-LOADING VS STATION')
1009 FORMAT ('0',T10,'CIRCUMFERENTIAL-LOADING VS STATION')
1010 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
1011 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
1012 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
1013 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
1014 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
1015 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
1016 FORMAT ('0',T10,'THERMAL-LOADING VS STATION')
C *****
END
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C *****
SUBROUTINE PLOT2(NTH)
C *****
THIS SUBROUTINE CALLS PLOTTING ROUTINES FOR APPROPRIATE (USER
C *****
SPECIFIED) OUTPUT QUANTITIES
C *****
IMPLICIT LOGICAL*1 ($)
COMMON /IBL4/ KMAX,KL
COMMON /BL19/ TH(36)
COMMON /BLPLOT/
1 2 3
COMMON /BLPLT1/
1 2 3 4 5 6
COMMON /BLPLT1/
C *****
NGKMAX=-KMAX
IF ($MODAL) GO TO 121
IF (INS.EQ.0) GO TO 4
WRITE (6,1000)
IF (INS.GT.0) CALL PLOTIT (XSTATN,YNS,KMAX,0)
IF (INS.LT.0) CALL PLOTIT (XSTATN,YNS,NGKMAX,0)
WRITE (6,1001) TH(NTH)
4 IF (INTH.EQ.0) GO TO 5
C *****
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WRITE (6,1000)
IF (INTH.GT.0) CALL PLOTTT (XSTATN,YNTH,KMAX,0)
IF (INTH.LT.0) CALL PLOTTT (XSTATN,YNTH,NGKMAX,0)
WRITE (6,1002) TH(NTH)
5 IF (INSTH.EQ.0) GO TO 6
WRITE (6,1000)
IF (INSTH.GT.0) CALL PLOTTT (XSTATN,YNSTH,KMAX,0)
IF (INSTH.LT.0) CALL PLOTTT (XSTATN,YNSTH,NGKMAX,0)
WRITE (6,1003) TH(NTH)
6 IF (IQS.EQ.0) GO TO 7
WRITE (6,1000)
IF (IQS.GT.0) CALL PLOTTT (XSTATN,YQS,KMAX,0)
IF (IQS.LT.0) CALL PLOTTT (XSTATN,YQS,NGKMAX,0)
WRITE (6,1004) TH(NTH)
7 IF (IMS.EQ.0) GO TO 8
WRITE (6,1000)
IF (IMS.GT.0) CALL PLOTTT (XSTATN,YMS,KMAX,0)
IF (IMS.LT.0) CALL PLOTTT (XSTATN,YMS,NGKMAX,0)
WRITE (6,1005) TH(NTH)
8 IF (IMTH.EQ.0) GO TO 9
WRITE (6,1000)
IF (IMTH.GT.0) CALL PLOTTT (XSTATN,YMTH,KMAX,0)
IF (IMTH.LT.0) CALL PLOTTT (XSTATN,YMTH,NGKMAX,0)
WRITE (6,1006) TH(NTH)
9 IF (IMSTH.EQ.0) GO TO 1211
WRITE (6,1000)
IF (IMSTH.GT.0) CALL PLOTTT (XSTATN,YMSTH,KMAX,0)
IF (IMSTH.LT.0) CALL PLOTTT (XSTATN,YMSTH,NGKMAX,0)
WRITE (6,1007) TH(NTH)
1211 IF (IU.EQ.0) GO TO 10
WRITE (6,1000)
IF (IU.GT.0) CALL PLOTTT (XSTATN,YU,KMAX,0)
IF (IU.LT.0) CALL PLOTTT (XSTATN,YU,NGKMAX,0)
WRITE (6,1010) TH(NTH)
10 IF (IV.EQ.0) GO TO 11
WRITE (6,1000)
IF (IV.GT.0) CALL PLOTTT (XSTATN,YV,KMAX,0)
IF (IV.LT.0) CALL PLOTTT (XSTATN,YV,NGKMAX,0)
WRITE (6,1009) TH(NTH)
11 IF (IW.EQ.0) GO TO 12
WRITE (6,1000)
IF (IW.GT.0) CALL PLOTTT (XSTATN,YW,KMAX,0)
IF (IW.LT.0) CALL PLOTTT (XSTATN,YW,NGKMAX,0)
WRITE (6,1008) TH(NTH)
12 IF (IPHIS.EQ.0) GO TO 13
WRITE (6,1000)
IF (IPHIS.GT.0) CALL PLOTTT (XSTATN,YPHIS,KMAX,0)
IF (IPHIS.LT.0) CALL PLOTTT (XSTATN,YPHIS,NGKMAX,0)

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13 WRITE (6,1011) TH(NTH)
   IF (IPHIT.EQ.0) GO TO 14
   WRITE (6,1000)
   IF (IPHIT.GT.0) CALL PLOTIT (XSTATN,YPHIT,KMAX,0)
   IF (IPHIT.LT.0) CALL PLOTIT (XSTATN,YPHIT,NGKMAX,0)
   WRITE (6,1012) TH(NTH)
   GO TO 21
14 WRITE (6,1000)
   IF (IPHI.GT.0) CALL PLOTIT (XSTATN,YPHI,KMAX,0)
   IF (IPHI.LT.0) CALL PLOTIT (XSTATN,YPHI,NGKMAX,0)
   WRITE (6,1013) TH(NTH)
   RETURN
21 IF (INS.EQ.0) GO TO 15
121 WRITE (6,1000)
   IF (INS.GT.0) CALL PLOTIT (XSTATN,YNS,KMAX,0)
   IF (INS.LT.0) CALL PLOTIT (XSTATN,YNS,NGKMAX,0)
   WRITE (6,2001)
   GO TO 16
15 WRITE (6,1000)
   IF (INTH.EQ.0) CALL PLOTIT (XSTATN,YNTH,KMAX,0)
   IF (INTH.GT.0) CALL PLOTIT (XSTATN,YNTH,NGKMAX,0)
   IF (INTH.LT.0) CALL PLOTIT (XSTATN,YNTH,NGKMAX,0)
   WRITE (6,2002)
   GO TO 17
16 WRITE (6,1000)
   IF (INSTH.GT.0) CALL PLOTIT (XSTATN,YNSTH,KMAX,0)
   IF (INSTH.LT.0) CALL PLOTIT (XSTATN,YNSTH,NGKMAX,0)
   WRITE (6,2003)
   GO TO 18
17 WRITE (6,1000)
   IF (IQS.GT.0) CALL PLOTIT (XSTATN,YQS,KMAX,0)
   IF (IQS.LT.0) CALL PLOTIT (XSTATN,YQS,NGKMAX,0)
   WRITE (6,2004)
   GO TO 19
18 WRITE (6,1000)
   IF (IMS.GT.0) CALL PLOTIT (XSTATN,YMS,KMAX,0)
   IF (IMS.LT.0) CALL PLOTIT (XSTATN,YMS,NGKMAX,0)
   WRITE (6,2005)
   GO TO 22
19 WRITE (6,1000)
   IF (IMTH.GT.0) CALL PLOTIT (XSTATN,YMTH,KMAX,0)
   IF (IMTH.LT.0) CALL PLOTIT (XSTATN,YMTH,NGKMAX,0)
   WRITE (6,2006)
   GO TO 231
22 WRITE (6,1000)
   IF (IMSTH.GT.0) CALL PLOTIT (XSTATN,YMSTH,KMAX,0)
   IF (IMSTH.LT.0) CALL PLOTIT (XSTATN,YMSTH,NGKMAX,0)
   WRITE (6,2007)
   IF (IU.EQ.0) GO TO 23
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WRITE (6,1000) CALL PLOTIT (XSTATN,YU,KMAX,0)
IF (IU.GT.0) CALL PLOTIT (XSTATN,YU,NGKMAX,0)
IF (IU.LT.0) CALL PLOTIT (XSTATN,YU,NGKMAX,0)
WRITE (6,2010) GO TO 24
23 WRITE (6,1000)
IF (IV.GT.0) CALL PLOTIT (XSTATN,YV,KMAX,0)
IF (IV.LT.0) CALL PLOTIT (XSTATN,YV,NGKMAX,0)
WRITE (6,2009) GO TO 25
24 WRITE (6,1000)
IF (IW.GT.0) CALL PLOTIT (XSTATN,YW,KMAX,0)
IF (IW.LT.0) CALL PLOTIT (XSTATN,YW,NGKMAX,0)
WRITE (6,2008) GO TO 26
25 IF (IPHS.EQ.0) GO TO 26
WRITE (6,1000) CALL PLOTIT (XSTATN,YPHIS,KMAX,0)
IF (IPHS.GT.0) CALL PLOTIT (XSTATN,YPHIS,NGKMAX,0)
IF (IPHS.LT.0) CALL PLOTIT (XSTATN,YPHIS,NGKMAX,0)
WRITE (6,2011) GO TO 27
26 IF (IPHT.EQ.0) GO TO 27
WRITE (6,1000) CALL PLOTIT (XSTATN,YPHIT,KMAX,0)
IF (IPHT.GT.0) CALL PLOTIT (XSTATN,YPHIT,NGKMAX,0)
IF (IPHT.LT.0) CALL PLOTIT (XSTATN,YPHIT,NGKMAX,0)
WRITE (6,2012) GO TO 28
27 IF (IPHI.EQ.0) GO TO 28
WRITE (6,1000) CALL PLOTIT (XSTATN,YPHI,KMAX,0)
IF (IPHI.GT.0) CALL PLOTIT (XSTATN,YPHI,NGKMAX,0)
IF (IPHI.LT.0) CALL PLOTIT (XSTATN,YPHI,NGKMAX,0)
WRITE (6,2013)
28 RETURN

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C*****
1000 FORMAT ('1',T10,'S'-MEMBRANE FORCE VS STATN, MERIDIAN AT THETA =
1001 1,F10.5,RADIANS')
1002 1,F10.5,RADIANS')
1003 1,F10.5,RADIANS')
1004 1,F10.5,RADIANS')
1005 1,F10.5,RADIANS')
1006 1,F10.5,RADIANS')
1007 1,F10.5,RADIANS')
1008 1,F10.5,RADIANS')

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1009 FORMAT ('0',T10,'CIRCUMFERENTIAL DEFLECTION VS STATN, MERIDIAN AT
1 THETA =',F10.5,' RADIANS')
1010 FORMAT ('0',T10,'MERIDIONAL DEFLECTION VS STATN, MERIDIAN AT THET
1A =',F10.5,' RADIANS')
1011 FORMAT ('0',T10,'MERIDIONAL ROTATION VS STATN, MERIDIAN AT THETA
1B =',F10.5,' RADIANS')
1012 FORMAT ('0',T10,'CIRCUMFERENTIAL ROTATION VS STATN, MERIDIAN AT T
1 THETA =',F10.5,' RADIANS')
1013 FORMAT ('0',T10,'MERIDIONAL ROTATION VS STATN, MERID
1IAN AT THETA =',F10.5,' RADIANS')
2001 FORMAT ('0',T10,'S-MEMBRANE FORCE VS STATION')
2002 FORMAT ('0',T10,'S-MEMBRANE FORCE VS STATION')
2003 FORMAT ('0',T10,'S-THESTATIVE SHEAR VS STATION')
2004 FORMAT ('0',T10,'S-THESTATIVE SHEAR VS STATION')
2005 FORMAT ('0',T10,'S-EFFECTIVE BENDING MOMENT VS STATION')
2006 FORMAT ('0',T10,'S-EFFECTIVE BENDING MOMENT VS STATION')
2007 FORMAT ('0',T10,'S-THESTA DEFLECTION VS STATION')
2008 FORMAT ('0',T10,'S-THESTA DEFLECTION VS STATION')
2009 FORMAT ('0',T10,'CIRCUMFERENTIAL DEFLECTION VS STATION')
2010 FORMAT ('0',T10,'MERIDIONAL DEFLECTION VS STATION')
2011 FORMAT ('0',T10,'MERIDIONAL DEFLECTION VS STATION')
2012 FORMAT ('0',T10,'CIRCUMFERENTIAL ROTATION VS STATION')
2013 FORMAT ('0',T10,'MERIDIONAL ROTATION VS STATION')
C *****
END

```

```

SUBROUTINE PLOTIT(X,Y,N,MODCUR)
C *****
C THIS SUBROUTINE AND THE THREE THAT FOLLOW IT COMPRISE THE SELF-
C CONTAINED PLOTTING CAPABILITY OF THE PROGRAM. SATANS. THEY RECEIVE
C THE DATA TO BE PLOTTED, ROUND IT, SCALE IT AND DRAW IT ON THE HIGH-
C SPEED LINE PRINTER.
C *****
DIMENSION X( 1),Y( 1), RANGES(4)
EQUIVALENCE (RANGES(1),XMAX), (RANGES(2),XMIN), (RANGES(3),YMAX),
1 (RANGES(4),YMIN)
KN=IABS(NN)
IF(MODCUR.GT.1) GO TO 5
C *****
C FIND MAX & MIN FOR SCALE COMPUTATIONS
C *****
XMAX=-1.E20
XMIN=1.E20
YMAX=-1.E20
YMIN=1.E20
DO 1 I=1,KN
IF(X(I).LT.XMAX) GO TO 6

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XMAX=X(I)
6 IF(X(I)-GT.XMIN) GO TO 7
XMIN=X(I)
7 IF(Y(I)-LT.YMAX) GO TO 8
YMAX=Y(I)
8 IF(Y(I)-GT.YMIN) GO TO 1
YMIN=Y(I)
1 CCNT=INUE
C IF NOT AUTOSCALE GO TO CALL DRAWIT
C IF(NN.GT.0) GO TO 5
C COMPUTE X-SCALE & NEW XMAX AND XMIN
C CALL SCALIT(XMAX,XMIN,4)
C COMPUTE Y-SCALE & NEW YMAX AND YMIN
C CALL SCALIT(YMAX,YMIN,6)
C PLOT CURVE
5 CALL DRAWIT(X,Y,KN,RANGE,S,1,MODCUR)
IF(MODCUR.EQ.1.CR.MODCUR.EQ.2) RETURN
PRINT SCALES WHEN LAST CURVE PLOTTED
XS=(XMAX-XMIN)/80.
YS=(YMAX-YMIN)/60.
WRITE(6,10) XS,YS
100 FORMAT(15X,'X-SCALE: ',15X,'Y-SCALE: ',15X)
1 RETURN
END
SUBROUTINE SCALIT(XMAX,XMIN,IDIV)
ROUND MAXIMUM TO NEXT HIGHEST 2 SIG FIGS
CIV=IDIV
XMAX=AMAX1(0.,XMAX)
CALL ROUND(XMAX,IMX,FMX)
IMX=IMX-1
FMX=FMX*10.
3 XMX=FMX*10.

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10 IF (DIV.GT.4) GO TO 15
C IF X SCALE BETWEEN 8. AND 10. ROUNDED TO 10.
C
FFX=ABS(FACTX/10.)
IF (FFX.GT.8. AND FFX.LT.10.) FFX=10.
IF (FACTX.LT.0.) FFX=-10.
FACTX=FFX
15 XSC=FACTX/10.
C COMPUTE NEW MAX & MIN FROM ROUNDED SCALE
C
IF (XM.NE.0.) GO TO 4
IF (XM.NE.0.) XMIN=-XSC
IF (XM.NE.0.) XMAX=XSC
RETURN
4 XMAX=XSC+XMN
XMIN=XMN
RETURN
END

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SUBROUTINE ROUNDA(ANUM,IS,FACT)
C EXPRESS ANUM IN SCIENTIFIC NOTATION WHERE
C ANUM=FACT*10. AND 1. AND 9.9
C IF (ANUM.EQ.0.) GO TO 15
BNUM=ANUM
IF (BNUM.LT.0.) BNUM=-BNUM
IS=ALOG(BNUM)*.43429448
FACT=BNUM/10.
C FIND POWER OF 10
IDC=-3
R2=0
DO 10 I=1,5
IDC=IDC+1
R1=R2
R2=10.*(IDC+1)
IF (FACT.GE.R1 AND FACT.LT.R2) GO TO 8
10 CONTINUE
8 FACT=FACT*10.*(-IDC)
IS=IS+IDC
C ROUND MANTISSA TO 2 SIG FIGS

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1  IERR=IERR+1
  IF(X(I).LE.XMAX) GO TO 205
  X(I)=XMAX
  GO TO 210
205 IF(X(I).GE.XMIN) GO TO 210
  X(I)=XMIN
210 IF(Y(I).LE.YMAX) GO TO 215
  Y(I)=YMAX
  GO TO 30
215 IF(Y(I).GE.YMIN) GO TO 30
  Y(I)=YMIN
30 CONTINUE
C** PLOTTING X AND Y AXIS, IF NECESSARY
C**
C** JERR=0
  X RANGE=XMAX-XMIN
  Y RANGE=YMAX-YMIN
  IF (Y RANGE.NE.0.) GO TO 298
  IF(YMIN.EQ.0.) GO TO 889
  YMIN=J
  Y RANGE=YMAX
  GO TO 299
298 IF (X RANGE.NE.0.) GC TO 299
  IF(XMIN.EQ.0.) GO TO 887
  XMIN=0
  X RANGE=XMAX
  BLANKING CUT MATRIX-(GRID)
C**
C** 299 DO 300 I=1,61
  DO 301 JJ=1,81
    GRID(I,JJ)=BLANK
  CONTINUE
300 IF(XMAX* XMIN.GE.0.) GO TO 222
  IYAXIS=80./(-XMIN)/X RANGE+1.5
  DO 40 I=1,61
    GRID(I,IYAXIS)=DCT
  40 GRID(I,IYAXIS)=DCT
  222 IF(YMAX* YMIN.GE.0.) GO TO 333
  IXAXIS=60./YMAX/Y RANGE+1.5
  DO 60 I=1,81
    GRID(IXAXIS,I)=DCT
  60 GRID(IXAXIS,I)=DCT
C**
C** COMPUTE PROPER SCALE NUMBERS
C**
333 XINCR=X RANGE/4.
  YINCR=Y RANGE/6.
  XSCALE(1)=XMAX

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18 FORMAT(3X,1PE10.3,2X,1H+,1X,81A1,1X,1H+,2X,E10.3)
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404 WRITE(6,118) YSCALE(11),(GRID(1K,IX),IX=1,81),YSCALE(11)
118 FORMAT(2X,F11.2,'+',81A1,'+',F11.2)
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SUBROUTINE RANGER (*)
C *****
C SUBROUTINE RANGER IS THE CONTROLLING SUBROUTINE FOR THE FREQUENCY
C RANGE SEARCH OPERATION. THE TOP AND BOTTOM OF THE RANGE IS CON-
C VERTED FROM CPS TO RADIANS/SEC AND A CHECK PERFORMED ON THE
C LIMITS. THE LOWEST (SUB. BTM) AND HIGHEST (SUB. TOPPER)
C FREQUENCIES ARE DETERMINED PRIOR TO THE RANGE BEING PARTITIONED.
C THE ALGORITHM IS BIAISED TOWARD THE LOWER FREQUENCIES. A FORM OF
C RATE-AITKIN EXTREME ADJUST IS USED TO INCREASE THE CONVERGENCE
C PARTICULAR CASE.
C *****
C IMPLICIT LOGICAL I ($ )
C REAL*8 ZERO, PTFIVE, CNEDO, SMALL, VREAL, VIMAG, EPSVIB, EPSVEC, EPSAIT,
C 9 SCALEW, SCALEX, SCALE3, VR, VI, WW, XX, YY, XAITKN, VALNEW, VALOLD, PCNT,
C 8 TWOPI, WV, XV, YV
C COMMON /BL24/ DG(4,4), RANGE(100,4), TOP, BOTTOM, DELSHF, TOLSHF, RZ(12)
C COMMON /BL100/ TEE0, $DYNMC
C COMMON /BL104/ WV(4,203), XV(4,203), YV(4,203), FILL(28), SHFTPT(3,100)
C COMMON /BLK2/ IVIBS, IVB
C COMMON /BLK3/ TWOPI, IFEVIN, IENDO, SMALL, VREAL, VIMAG, AREAL
C COMMON /BLK4/ ZERO, PTFIVE, ONEC
C COMMON /BLK5/ $FLAG, $TAG, $DOVEC
C COMMON /BLK6/ NJ, NK, I4, IRGOLD, NUMBER, ITWO
C COMMON /BLK7/ SCALEX, SCALEW, SCALE3
C COMMON /BLK8/ EPSVIB, EPSVEC, EPSAIT
C COMMON /BLK9/ ITRI, ITR2
C COMMON /BLK10/ ASHIFT, ATSHF, PI1, TOLUP, TOLDWN, TOLCLS
C COMMON /BLK13/ DIF1, DIF2, DIF3, DIF4, TOLLOW, TOLHI, TOLRNG
C XAITKN(WW,XX,YY) = WV - (((WW-XX)*2)/((WW+YY)-(2.0*XX)))
C *****
C BOTTOM = -((SHFTPT(1,IVB) * SNGL(TWOPI) * TEE0)**2)
C TOP = -((SHFTPT(2,IVB) * SNGL(TWOPI) * TEE0)**2)
C CALL VECOUT(1, &1)
C CALL VECOUT(1, &1)
C IF(BOTTOM.LE.-TOP) CALL VECOUT(4, &9)
C CALL BOTTOM( &9)
C CALL TOPPER( &9)
C IRGOLD = 1
C IF(IRGOLD.LE.0) CALL VECOUT(19, &9)
C I4 = 1
C VALNEW = ZERO
C $TAG = .FALSE.
C IF(RANGE(I4,2).LE.(TOLRNG*RANGE(I4,3))) CALL ADJUST(1, &2, &2)
C $TAG = .TRUE.
C DELR = (RANGE(I4,3) - RANGE(I4,2)) * TOLCLS
C ASHIFT = RANGE(I4,2) +

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DELSHF = RANGE(I4,3) - DELR
WRITE(6,333) I4,(RANGE(I4,J),J=1,4),(RANGE(I4+1,K),K=1,4)
FORMAT(//35X,'RANGE',I2,'=',4E14.6//35X,'RANGE',I2,'=',4E14.6)
CALL STARTX(2)
CALL PMATRIX
DO 4 I5 = 1,ITR1
$FLAG = .TRUE.
CALL ITRATE
VALCLO = VALNEW
VALNEW = XAITKN(SCALEW,SCALEX,SCALE3)
PCNT=DABS((DABS(VALNEW)-DABS(VALCLO))/VALNEW)
IF(NJ.GT.I.TR2) CALL VECOUT(7,&4)
IF(PCNT.LT.EPSAIT.AND.NJ.GT.3) GO TO 8
CONTINUE
CALL VECOUT(8,&5)
CALL ITCPLX(&6)
IF($FLAG) CALL ADJUST(5,&7,&2)
CALL ADJUST(1,&7,&2)
$TAG = .FALSE.
ASHIFT = DELSHF
GO TO 3
DIF1 = TOLLOW * RANGE(I4,1)
DIF2 = TOLHI * RANGE(I4,1)
VREAL = CHEDD / VALNEW
VREAL = DBLE(ASHFAL)
AREAL = SNGL(VREAL)
IF(AREAL.LE.DIF1.AND.AREAL.GE.DIF2) CALL ADJUST(2,&7,&2)
DIF3 = TOLLOW * RANGE(I4,4)
DIF4 = TOLHI * RANGE(I4,4)
IF(AREAL.LE.DIF3.AND.AREAL.GE.DIF4) CALL ADJUST(3,&7,&2)
IF(AREAL.LE.DIF2.AND.AREAL.GE.DIF3) CALL ADJUST(4,&7,&2)
IF(AREAL.GT.DIF1.OR.AREAL.LT.DIF4) CALL ADJUST(1,&7,&2)
RETURN
END

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SUBROUTINE ADJUST(IADJ,*)
THIS SUBROUTINE, CALLED BY SUBROUTINE RANGER, PERFORMS THE FINAL
DISPOSITION OF EACH SEARCH POINT WHEN A NEW RECKED EIGENVALUE
IS DETERMINED (IADJ=7). IT IS REFINED, RANGE PARAMETERS CALC-
ULATED FOR RANGE, AND EVENT THE EIGENVALUE FALLS
OUT OF THE RANGE, OR A SUITABLE POSITION THEREOF, IS ELIMINATED.
THE TOTAL RANGE, OR A SUITABLE POSITION THEREOF, IS ELIMINATED.

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IMPLICIT LOGICAL*1 ($)
REAL*8 ZERO,CO,P,FIVE,ONE,FO,SMALL,VREAL,VIMAG
COMMON/BLK24/DG(4,4,4),RANGE(IJJ,4),TOP,BOTTOM,DELSHF,TOLSHF,RZ(12)
COMMON/BLK4/ZERO,CO,P,FIVE,ONE,FO,SMALL,VREAL,VIMAG,AREAL
COMMON/BLK5/$FLAG,$TAG,$COVEC
COMMON/BLK6/NJ,NK,I4,IRGOLD,NUMBER,ITWO
COMMON/BLK10/ASHIFT,ASHFUM,ATSHF,BIT,TOLUP,TOLDWN,TOLCLS
COMMON/BLK13/DIF1,DIF2,DIF3,DIF4,TOLLOX,TOLHI,TOLRNG
C*****
GO TO (1,3,4,7,12),IADJ
1 IF($TAG) RETURN 1
5 DO 2 J = 1,4
DO 2 I = 1,4,IRGOLD
IPI = I + 1
2 RANGE(I,J) = RANGE(IPI,J)
IRGOLD = IRGOLD - 1
RETURN 2
3 RANGE(I4,2) = ASHFUM + (ASHFUM - RANGE(I4,1))
IF($TAG) RETURN 1
GO TO 6
4 RANGE(I4,3) = ASHFUM - (RANGE(I4,4) - ASHFUM)
6 IF(RANGE(I4,2).LE.(TOLRNG*RANGE(I4,3))) GO TO 5
IF($TAG) RETURN 1
RETURN 2
7 ASHFUM = ASHFUM + TOLSHF * (AREAL - ASHFUM)
ARNG1 = ASHFUM
CALL PMATRX
CALL ITREAL(E8)
CALL ITREAL(E1)
GO TO 1
8 ASHFUM = ARNG1
DIF1 = TOLLOX * RANGE(I4,1)
DIF2 = TOLHI * RANGE(I4,1)
DIF3 = TOLLOX * RANGE(I4,4)
DIF4 = TOLHI * RANGE(I4,4)
IF(AREAL.LE.DIF1.AND.AREAL.GE.DIF2) GO TO 3
IF(AREAL.LE.DIF3.AND.AREAL.GE.DIF4) GO TO 4
IF(AREAL.GT.DIF1.OR.AREAL.LT.DIF4) GO TO 1
CALL VECOUT(9,E9)
GO TO 1
9 IM1 = IRGOLD + 2
DO 10 J = I4,IRGOLD
DO 10 I = IM1 - 1
IM2 = IM1 - 1
10 RANGE(IM1,I) = RANGE(IM2,I)
IRGOLD = IRGOLD + 1
NUMBER = NUMBER + 1
RANGE(I4,3) = AREAL

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RANGE(I4,4) = AREAL
RANGE(I4+1,1) = AREAL
RANGE(I4+1,2) = AREAL
IF(RANGE(I4,2).LE.(TOLRNG*RANGE(I4,3))) GO TO 5
GO TO (11,14,16),ITWO
11 RETURN 2
12 DIF1 = TOLLOW * RANGE(I4,1)
DIF2 = TOLLOW * RANGE(I4,1)
DIF3 = TOLLOW * RANGE(I4,4)
DIF4 = TOLLOW * RANGE(I4,4)
AREAL = SNGL(VREAL)
AREAL = SNGL(VIMAG)
IF((BREAL.GE.DIF4.AND.BREAL.LE.DIF3).AND.(AREAL.GE.DIF2.AND.AREAL.
1 LE.DIF1)) GO TO 5
IF(BREAL.GE.DIF4.AND.BREAL.LE.DIF3) RANGE(I4,3) = ASHFUM
IF(AREAL.GE.DIF2.AND.AREAL.LE.DIF1) RANGE(I4,2) = ASHFUM
IF((AREAL.GT.DIF1.CR.AREAL.LT.DIF4).AND.(BREAL.LT.DIF4.OR.BREAL.GT
1 DIF1)) GO TO 1
IF((AREAL.LT.DIF2.AND.AREAL.GT.DIF3).AND.(BREAL.LT.DIF2.AND.BREAL
1 GT.DIF3)) GO TO 13
IF((AREAL.LT.DIF4.OR.AREAL.GT.DIF1).AND.(BREAL.GT.DIF3.AND.BREAL.L
1 T.DIF2)) GO TO 18
IF((BREAL.LT.DIF4.OR.BREAL.GT.DIF1).AND.(AREAL.GT.DIF3.AND.AREAL.L
1 T.DIF2)) GO TO 17
13 RETURN 2
DIST1 = ABS(ASHFUM - BREAL)
DIST2 = ABS(AREAL - ASHFUM)
ATEMP = AREAL
IF(DIST2.GT.DIST1) GO TO 15
ITWO = 2
GO TO 7
14 AREAL = BREAL
I4 = I4 + 1
CALL START(2)
GO TO 7
15 AREAL = BREAL
ITWO = 3
GO TO 7
16 AREAL = ATEMP
CALL START(2)
GO TO 7
17 ITWO = 1
GO TO 7
18 AREAL = BREAL
ITWO = 1
GO TO 7
END

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C** SUBROUTINE BTIM(*)
C**
C** SUBROUTINE BTIM DETERMINES THE LOWEST FREQUENCY IN THE OVERALL
C** RANGE OF THE CONVERGENCE TEST ON THE VECTOR IS ALWAYS PERFORMED.
C** A FORM OF THE AKIN EXTRAPOLATION IS USED TO INCREASE THE CON-
C** VERGENCE RATE. THE RANGE WILL BE SEARCHED BOTTOM TO TOP IN PRE-
C** DETERMINED SEGMENTS UNTIL A REAL EIGENVALUE IS DETERMINED AS
C** THE BOTTOM (TOLUP AND NTRY IN SUBROUTINE INITAA).
C**
C** IMPLICIT LOGICAL(*)
C** REAL*8 ZERO, PTFIVE, ONEDO, SMALL, VREAL, VIMAG, EPSVIB, EPSVEC, EPSAIT,
C** 9 SCALEW, SCALEX, SCALES, VR, VI, WW, XX, YY, XAI, TKN, TEMPI, TEMP2, TEMP3,
C** 8 TWOPI, CLDVR
C** COMMON/BLK24/DG(4,4,4), RANGE(100,4), TOP, BOTTOM, DELSHF, TOLSHF, RZ(12)
C** COMMON/BLK4/ZEROCO, PTFIVE, ONEDO, SMALL, VREAL, VIMAG, AREAL
C** COMMON/BLK5/$FLAG, $TAG, $DOVEC
C** COMMON/BLK6/NJ, NK, I4, IRGOLD, NUMBER, ITWO
C** COMMON/BLK7/SCALEX, SCALEW, SCALE3
C** COMMON/BLK8/EPSVIB, EPSVEC, EPSAIT
C** COMMON/BLK9/ITR1, ITR2
C** COMMON/BLK10/ASHIFT, ASHFUM, ATSHF, BII, TOLUP, TOLDWN, TOLCLS
C** COMMON/BLK12/NTRY
C** SIZE(VR, VI) = - SNGL(DSORT(VR*VR + VI*VI))
C** XAI, TKN(WW, XX, YY) = EW - (((WW-XX)*2)/((WW + YY)-(2.0 * XX)))
C**
C** $TAG = $DOVEC
C** $DOVEC = .TRUE.
C**
C** NI = 1
C** DELSHF = TOLUP * (TOP - BOTTOM)
C** DO 8 I = 1, 4
C** 1 RANGE(2, I) = 0.0
C** IF (BOTTOM.LE.TOP) CALL VECOUT(11, &5)
C** IF (NTRY) CALL VECOUT(12, &5)
C** IF (NI.GT.1)
C** CALL START(1)
C** ASHIFT = BOTTOM
C** CALL PMATX, ITR1
C** DO 9 I = 1, ITR1
C** $FLAG ITRATE
C** CALL ITRATE
C** TKN(SCALEW, SCALEX, SCALE3)
C** XAI, TKN(TEMP1)
C** TEMP1 = CABS(TEMP1)
C** TEMP2 = CABS((TEMP2 - CLDVR)/TEMP2)
C** TEMP3 = TEMP2
C** CLDVR = TEMP2
C** IF (NJ.GT.1) CALL VECOUT(7, &9)
C** IF (TEMP3.GE.EPSAIT)
C** IF (NJ.LT.3) GO TO 9
C** IF (NJ.LT.3) GO TO 9
C** VREAL = (ONEDO/TEMP1) + DBLE(ASHFUM)

```



```

11 11 ASHIFT = ASHFUM + TOLSHF * (SNGL(VREAL) - ASHFUM)
    IF (ABS(ASHIFT).LE.1.0) GO TO 11
    CALL PMATRIX
    CALL ITREAL(86)
    GO TO 11
19 19 CONTINUE
    CALL VECOUT(8,&10)
13 13 ARTSIZ = 0.0
    CALL TCPLX(&2)
    IF ($FLAG) GO TO 6
    ARTSIZ = SIZE(VREAL,VIMAG)
    BOTTOM = BOTTOM + DELSHF
2 2 IF (ARTSIZ.LT.BOTTCM) BOTTOM = BOTTOM - DELSHF + 1.1 * ARTSIZ
    CALL VECOUT(10,&1)
6 6 AREAL = SNGL(VREAL)
    AIMAG = SNGL(VIMAG)
    DIST1 = ABS(AIMAG - BOTTOM)
    DIST2 = ABS(AREAL - BOTTOM)
    IF (DIST1.LT.DIST2.AND.VIMAG.LT.ZERODO) AREAL = AIMAG
    NUMBER(1,1) = AREAL
    $DOVEC = 1
    IF (AREAL.LE.BOTTCM) RANGE(1,2) = AREAL
    IF (AREAL.GT.BOTTCM) RANGE(1,2) = BOTTOM
    CALL VECOUT(20,&3)
3 3 IF (VIMAG.EQ.ZERODO) CALL VECOUT(9,&7)
7 7 IF (RANGE(1,2).LE.TOP) CALL VECOUT(11,&5)
5 5 RETURN
    END

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C ***** SUBROUTINE TOPPER(*) *****
C ***** SUBROUTINE TOPPER DETERMINES THE HIGHEST FREQUENCY IN THE OVERALL *****
C ***** RANGE. IT OPERATES IN A MANNER SIMILAR TO SUBROUTINE BTM. *****
C ***** IMPLICIT LOGICAL*11 ($) *****
    REAL*8 ZERODO,PTFIVE,QNFED3,SMALL,VREAL,VIMAG,EPVIB,EPVSEC,EPVSAIT,
9 SCALEX,SCALE3,VX,VI,VW,XX,YY,XAITKN,TEMP1,TEMP2,TEMP3,
8 TWOPI,OLDVR
    COMMON/BLK24/DG(4,4,4),NAGE(100,4),TOP,BOTTOM,DELSHF,TOLSHF,RZ(12)
    COMMON/BLK4/ZERODO,BTTCM,QNFED3,PTFIVE,OLDVEC
    COMMON/BLK5/$FLAG,$TAG,$DOVEC
    COMMON/BLK6/NJ,NK,I4,IRGOLD,NUMBER,ITWO
    COMMON/BLK7/SCALEX,SCALE3
    COMMON/BLK8/EPVIB,EPVSEC,EPVSAIT
    COMMON/BLK9/ITR1,ITR2

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COMMON/BLK13/ASHIFT,ASHFUM,ATSF,F,BII,TOLUP,TOLDWN,TOLCLS
COMMON/BLK12/NTRY
SIZE(VR,VI) = - SNGL(DSORT(VR*VR + VI*VI))
XAITKN(WW,XX,YY) = WW - ((WW-XX)**2)/((WW + YY)-(2.0 * XX)))
C** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** ** **
IF(TOP .EQ. 0.0) TOP = -1000.0
NI = 1
1 IF(RANGE(1,2),LE.TOP) CALL VECOUT(13,&5)
IF(NI.GT.NTRY) CALL VECOUT(14,&5)
NI = NI + 1
CALL START(2)
ASHIFT = TOP
CALL PMATRIX
DO 9 I = 1,ITR1
$FLAG = .TRUE.
CALL ITRATE
TEMP1 = XAITKN(SCALEW,SCALEX,SCALE3)
TEMP2 = DABS(TEMP1)
TEMP3 = DABS((TEMP2 - OLDVR)/TEMP2)
OLDVR = TEMP2
IF(NJ.GT.ITR2) CALL VECOUT(7,&9)
IF(TEMP3.GE.EP$AIT) GO TO 9
IF(NJ.LT.3) GO TO 9
VREAL = (ONEDO/TEMP1) + DBLE(ASHFUM)
ASHIFT = ASHFUM + TOLSHF * (SNGL(VREAL) - ASHFUM)
CALL PMATRIX
CALL ITRREAL(&6)
GO TO 10
CONTINUE
9 CALL VECOUT(8,&10)
10 ARTSIZ = 0.0
CALL ITCPLX(&2)
IF($FLAG) GO TO 6
ARTSIZ = SIZE(VREAL,VIMAG)
2 TOP = TOP - DELSHF
TOP = TOP + DELSHF - 1.1 * ARTSIZ
6 CALL VECOUT(15,&1)
AREAL = SNGL(VREAL)
AIMAG = SNGL(VIMAG)
DIST1 = ABS(AIMAG - TOP)
DIST2 = ABS(AREAL - TOP)
IF(DIST1.LT.DIST2.AND.VIMAG.LT.ZERODO) AREAL = AIMAG
NUMBER = 2
IF(AREAL.GT.TOP) RANGE(1,3) = AREAL
IF(AREAL.LE.TOP) RANGE(1,3) = TOP
CALL VECOUT(21,&3)
3 IF(VIMAG.EQ.ZEROCC) CALL VECOUT(9,&7)

```



```

7 IF(RANGE(1,2).LE.RANGE(1,3)) CALL VECOUT(11,55)
4 RETURN
5 END

```

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C** SUBROUTINE ITRREAL(*)
C** THIS SUBROUTINE DIRECTS THE ITERATION PROCESS THAT DETERMINES
C** REAL EIGENVALUES AND VECTORS. THE CONVERGENCE TEST ON THE EIGEN-
C** VALUES IS PERFORMED IN THIS SUBROUTINE.
C** IMPLICIT LOGICAL I(*)
C** REAL*8 ZERO,PTFIVE,CNEDO,SMALL,VREAL,VIMAG,EPVSIB,EPSAIT,
1 SCALEW,SCALEX,SCALE3,CNEDVR,OLDVR,TEMP,WV,XV,YV
C** COMMON /I8L12/ KMAX1,KMAX2,NCCNV
C** COMMON /BLK1/ VMAS,NM2,$VIBES
C** COMMON /BLK4/ ZEROC,PTFIVE,CNEDO,SMALL,VREAL,VIMAG,AREAL
C** COMMON /BLK5/ $FLAG,$TAG,$DOVEC
C** COMMON /BLK6/ NJ,NK,I4,IRGCLOD,NUMBER,ITWO
C** COMMON /BLK7/ SCALEX,SCALEW,SCALE3
C** COMMON /BLK8/ EPVSIB,EPVSVC,EPSCAIT
C** COMMON /BLK9/ ITR1,ITR2
C** COMMON /BLK10/ ASHIFT,ACNEDUM,ATSHF,CJ1,TOLUP,TOLDWN,TOLCLS
C** $FLAG = .TRUE.
NN2 = 2
DO 17 ITR1 = 1,ITR1
CALL ITRATE ITR2) GO TO 20
IF(NJ.GT.CABS(SCALEW)
TEMP = CABS((TEMP - OLDVR)/TEMP)
OLDVR = TEMP
IF(CNEDVR.GT.EPVSIB) GO TO 17
IF($DOVEC .AND. (NCCNV .EQ. 0)) GO TO 17
NN2 = 1
CALL ITRATE
VREAL = CNEDO / SCALEW
VREAL = VREAL + DBLE(ATSHF)
AREAL = SNGL(VREAL)
RETURN 1
CONTINUE
20 VREAL = CNEDO / SCALEW
VREAL = VREAL + DBLE(ATSHF)
AREAL = SNGL(VREAL)
CALL VECOUT(7,817)
CONTINUE
17 VREAL = CNEDO / SCALEW

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```

VREAL = VREAL + DBLE(ATSHF)
AREAL = SNGL(VREAL)
CALL VECOUT(8,619)
19 RETURN
END

```

```

SUBROUTINE ITRATE
C ***
C THIS SUBROUTINE PERFORMS THE ITERATION COMPUTATIONS. POTTERS,
C SCHEME IS USED (EQUATION 29A AND 29B OF REF. 1). THE RAYLEIGH
C QUOTIENT IS CALCULATED AND THE VECTOR SCALED. IN
C ADDITION IF THE VECTOR CONVERGENCE TEST IS TO BE PERFORMED IT IS
C PERFORMED IN THIS SUBROUTINE.
C ***
C IMPLICIT LOGICAL*1 ($),PSAIT,CNEDC,PTFIVE,SCALEW,SCALEX,SCALE3,
C REAL*8 EPSVIB,EPSVEC,SUM1,TEMPW,TEMPX,TWOPI,VREAL,VIMAG,WV,XV,YV,
C 1 SMALL,SUM,ZV,TEMPY,TEMPY,WT,XT,YT
C 2 ZEROCD,ZI,ZV,TEMPY,TEMPY,WT,XT,YT
C ***
COMMON /BL3/ N0,M1,M2,M3
COMMON /BL4/ NMAX,KL
COMMON /BL5/ IBCINL,IBCFAL
COMMON /BL12/ KMAX1,KMAX2,NCONV
COMMON /BL1/ A(4,4),SEE(4,4),C(4,4)
COMMON /BL4/ P(4,4,200),ZFIM(4,4,10),ZF2M(4,4,10),ZF3M(4,4,10),
C 1 COMMON/BL24/DG(4,4,4),RA,GE(100,4),TOP,BOTTOM,DELSHF,TOLSHF,RZ(12)
COMMON/BL34/ DCE(4,4,200),DST(4,4,200)
COMMON/BL104/ WV(4,4,203),XV(4,4,203),YV(4,4,203),FILL(28),SHFTPT(3,100)
COMMON/BLK1/ VMAS,N2,PVIBES
COMMON/BLK3/ TWCP1,IBEP1VE,ONEDO,SMALL,VREAL,VIMAG,AREAL
COMMON/BLK4/ ZEROCD,PTFIVE,SCOVEC
COMMON/BLK5/ $ELAG,$TAG,$GOLD,NUMBER,ITWD
COMMON/BLK6/ NJ,NK,I4,I2GOLD,NUMBER,ITWD
COMMON/BLK7/SCALEX,SCALEW,SCALE3
COMMON/BLK8/ EPSVIB,EPSVEC,EPSAIT
C DIMENS:CN,ZV(4,200),ZT(4),ST(4),IPIVOT(4),INDEX(4,2),CLO(4,4),
C 4 EQUIVALENCE CLO(4,4),CL2(4,4),WT(812),YT(812)
C 3 (FILL(1),ZT(1)),(FILL(9),ST(1)),(CLO(1,1),ZFIM(1,1,1))
C 2 ((CL1(1,1),ZF2M(1,1,1)),(CL2(1,1),ZF3M(1,1,1)),
C ((WV(1,1),WT(1)),(XV(1,1),YV(1,1)),YT(1))
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C INCREMENT THE ITERATION COUNTERS.
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C 988
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C 991
C 992
C 993
C 994
C 995
C 996
C 997
C 998
C 999
C 1000

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```

C RETAIN THE LAST TWO SOLUTIONS.
SCALE3 = SCALEX
SCALEX = SCALEW
DO 102 I = IGO, ISTOP
102 Y(I) = XT(I)
DO 103 I = IGO, ISTOP
103 XT(I) = WT(I)
C MULTIPLY THE RIGHT HAND SIDE VECTOR BY THE DIAGONAL
C OF THE MASS MATRIX (W(J,203), J=1,4).
DO 104 J = IBEGIN, IEND
104 W(J,I) = W(J,I) * W(J,203)
C BEGIN FORWARD PASS.
C INITIAL POLE BOUNDARY CONDITIONS ON ZV ARE ZV(J,1)=0 FOR J=1,4.
C IF (BCINL.GE. 0) GO TO 106
DO 105 J = 1,4
105 ZV(J,1) = ZERO
106 DO 3 I = 1,4
SUM = ZERO
ZT(I) = W(I,2)
DO 2 J = 1,4
2 SUM = SUM + DBLE(DG(I,J,1)) * W(J,2)
3 ZV(I,1) = SUM
C FORWARD PASS LOOP.
DO 4 K = 2, KL
KM1 = K - 1
DO 6 I = 1,4
SUM = ZERO
DO 5 J = 1,4
5 SUM = SUM + DBLE(DEE(I,J,K)) * W(J,KP1) * ZV(J,KM1)
6 ZV(I,K) = SUM
7 CONTINUE
C COMPLETE FORWARD PASS AND BEGIN BACKWARD PASS.
C FINAL POLE BOUNDARY CONDITIONS
C ARE HANDLED IN STATEMENTS 20 THRU 29.

```



```

C THE FOLLOWING BLOCK OF STATEMENTS DETERMINE WV(J,KMAX1)
C FOR A SHELL WITH A FINAL POLE.
C
20 DO 201 J = 1,4
201 WV(J,KMAX1) = ZEROCC
    IF(M2.EQ.0) GO TO 23
    DO 22 I = 1,4
    SUM = ZEROCC
    DO 21 J = 1,4
    SUM = SUM + DBLE(CI2(I,J)) * ZV(J,KL)
21 SUM = SUM + DBLE(CI2(I,J)) * ZV(J,KL)
22 WV(I,KMAX1) = SUM
23 IF(M1.EQ.0) GO TO 26
    DO 25 I = 1,4
    SUM = ZEROCC
    DO 24 J = 1,4
    SUM = SUM + DBLE(CI1(I,J)) * ZV(J,KL)
24 SUM = SUM + DBLE(CI1(I,J)) * ZV(J,KL)
25 WV(I,KMAX1) = SUM
26 IF(M0.EQ.0) GO TO 29
    DO 28 I = 1,4
    SUM = ZEROCC
    DO 27 J = 1,4
    SUM = SUM + DBLE(CI0(I,J)) * ZV(J,KL)
27 SUM = SUM + DBLE(CI0(I,J)) * ZV(J,KL)
28 WV(I,KMAX1) = SUM
29 ISTART = 2
    GO TO 12
C
C CALCULATE EIGENVALUE AND SCALE SOLUTION VECTOR.
C
30 TEMPV = ZEROCC
    IF($FLAG) GO TO 302
    IF $FLAG IS FALSE ITRATE CALLED IN ITCPLX.
    DETERMINE AND SCALE BY THE MAXIMUM(ABSOLUTE) ELEMENT AND RETURN.
C
    DO 301 I = 160,1STOP
    TEMPW = WT(I)
    TEMPX = DABS(TEMPW)
    IF(TEMPX.LE. TEMPV) GO TO 301
    TEMPV = TEMPX
    TEMPY = TEMPW
301 CONTINUE = TEMPY
    SCALEW = TEMPY / TEMPV
    TEMPW = ONECC / TEMPY
    GO TO 31
C
C IF $FLAG IS TRUE ITRATE CALLED IN ITREAL,RANGER,BTMM CR TOPPER.
C
C CALCULATE RAYLEIGH QUOTIENT EIGENVALUE AND

```



```

C *** DETERMINE THE MAXIMUM(ABSOLUTE) ELEMENT. ***
302 SUM = ZERO
DO 303 I = 1,4
  TEMPW = WV(J,I) * WV(J,I)
  SUM = SUM + TEMPW
  IF(TEMPW .GT. TEMPV) GO TO 303
  TEMPV = TEMPW
303 CCCONTINUE
  SCALEW = SUM / SUM1
  IF NN2 = 2 SCALE BY MAXIMUM ELEMENT AND RETURN.
  GO TO (304,31),NN2
  IF NN2 = 1 SOLUTION HAS CONVERGED TO A REAL EIGENVALUE.
  SCALE VECTOR BY RAYLEIGH QUOTIENT. LAST SOLUTION ( THE
  COMPUTE DIFFERENCE BETWEEN THIS AND NEXT STARTING VECTOR FOR THE NEXT EIGENVALUE ). RETURN.
  TEMPW = SUM1 / SUM
  NN2 = 2
  VIMAG = ZERO
  DO 305 I = 1,4, ISTOP
    WT(I) = WT(I) * TEMPW
    YT(I) = YT(I) - WT(I)
  305 RETURN
  31 NCGNV = 1
  VIMAG = ZERO
  SCALE VECTOR BY THE MAXIMUM ELEMENT.
  DO 311 I = 1,4, ISTOP
    WT(I) = WT(I) * TEMPW
  311 WT(I) = WT(I)
  THE FOLLOWING BLOCK OF STATEMENTS PERFORM $DOVEC IS TRUE.
  TEST ON THE EIGENVECTOR. EXECUTED WHEN $DOVEC IS TRUE.
  IF(.NOT.$DOVEC) RETURN

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41600
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41690
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41770
41780

```

COMMON/BLK7/SCALEX,SCALEW,SCALEZ
COMMON/BLK8/EP$VIB,EP$SAIT
COMMON/BLK9/ITR1,ITR2
COMMON/BLK10/ASHIFT,ASHFUM,ATSHF,BII,TOLUP,TOLDWN,TOLCLS
COMMON/BL104/WV(4,203),XV(4,203),YV(4,203),SHFTPT(3,100)
DIMENSION WT(812),XT(812),YT(812)
EQUIVALENCE (WV(1,1),WT(1)),(XV(1,1),XT(1)),(YV(1,1),YT(1))
C*****
CALL START(1)
OLDVR = ZERODD
OLDVI = ZERODD
SCALEW = CNEODD
DO 5 I1 = 1,ITR1
$FLAG = .FALSE.
CALL ITRATE
B = ZERODD
C = ZERODD
D = ZERODD
F = ZERODD
DO 1 I = 1,IGC,1 STOP
1 B = B + XT(I)*XT(I)
2 C = C + XT(I)*XT(I)
3 D = D + XT(I)*XT(I)
4 F = F + XT(I)*XT(I)
9 DO 9 I = 1,IGC,1 STOP
G = G + YT(I)*YT(I)
H = H + YT(I)*YT(I)
B = B**SCALEX**SCALEW
C = C**SCALEX**SCALEW
D = D**SCALEX**SCALEW
G = G**C/B
H = H**C/B
IF(H.EQ.ZERODD) H = SMALL
ZC = D/B
C = (G-E*ZC)/H
P = ZC - U*Q
IF(Q.EQ.ZERODD) Q = -SMALL
ZB = ONEODD/Q
ZA = -P*ZB
VREAL = PTFIVE*ZA
VRO = ZB**4*DO**ZB
IF(RAD*GE*ZERODD)$FLAG = .TRUE.
IF(RAD*LT*ZERODD) RAD = -RAD
VIMAG = PTFIVE*DSQRT(RAD)

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41790
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41870
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41900
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41950
41960
41970
41980
41990

```
IF(DABS(VREAL)-LT.(1.D-13)) VREAL = SMALL
IF(CABS(VIMAG)-LT.(1.D-13)) VIMAG = SMALL
DELVR = CABS((CABS(VREAL)-CABS(OLDCV))/VREAL)
OLDCV = VREAL
DELVI = CABS((CABS(VIMAG)-CABS(OLDVI))/VIMAG)
OLDVI = VIMAG
VREAL = VREAL + DBLE(ATSHF)
IF(NJ.GT.ITR2) CALL VECOUT(16,85)
IF(DELVR.GT.EPSVIB) GO TO 5
IF(DELVI.GT.EPSVIB) GO TO 5
IF($FLAG) GO TO 8
CALL VECOUT(18,86)
5 CONTINUE
CALL VECOUT(16,87)
8 TEMP = VIMAG
VIMAG = VREAL - TEMP
VREAL = VREAL + TEMP
CALL VECOUT(17,86)
6 RETURN
7 END
```

42000
42010
42020
42030
42040
42050
42060
42070
42080
42090
42100
42110
42120
42130
42140
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42160
42170
42180
42190
42200
42210
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42230
42240

```
SUBROUTINE INITAA
C *** THIS SUBROUTINE SETS THE OPERATING PARAMETERS ***
C *** OF THE PROGRAM FOR THE VIBRATION ANALYSES. ***
C ***
C *** IMPLICIT LOGICAL*1 ($) ***
C *** REAL*8 ZERO,PTFIVE,DNEDO,SMALL,VREAL,VIMAG,EPSVIB,EPSAIT, ***
C *** TWOPI,WV,XV,YV ***
C ***
C *** 1 COMMON /IBL1/ MNMAX ***
C *** COMMON /IBL2/ N(10),MNINIT ***
C *** COMMON /IBL4/ KMAX,KL ***
C *** COMMON /IBL5/ IBCINL,IBCFNL ***
C *** COMMON/IBL7/ MNMAXO,MAXD(10),MAXS(10),MAXSY(10),MODVIB(3,100),ITEM ***
C *** IP(110) ***
C *** COMMON /IBL9/ MAXM ***
C *** COMMON /IBL10/ IFEREC,NTHMAX ***
C *** COMMON /IBL12/ KMAX1,KMAX2,NCONV ***
C *** COMMON /IBL13/ ITRMAX,LCSMAX ***
C *** COMMON /BL6/ SOE,OSE,ALCAD ***
C *** COMMON/IBL16/ EPS ***
C *** COMMON/BL24/DG(4,4,4),RANGE(100,4),TOP,BOTTOM,DEL SHF,TOL SHF,RZ(12) ***
C *** COMMON /BL100/ TEEC,$DYRMC ***
C *** COMMON /BL102/ DELOAD ***
C *** COMMON/BL104/ WV(4,203),XV(4,203),YV(4,203),FILL(28),SHFTPT(3,100) ***
C *** COMMON /BLK1/ VMAS,NK2,$VIRIES ***
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```

42250 COMMON /BLK3/ TWOPI,IBEGIN,IEND,IGC,ISTOP
42260 COMMON /BLK4/ ZEROODC,PTFIVE,ONEDO,SMALL,VREAL,VIMAG,AREAL
42270 COMMON /BLK8/ EPSVIB,EPSVIB2,EPSSVEC,EPSSAIT
42280 COMMON /BLK9/ ITR1,ITR2,ASHFUM,ATSHF,BII,TOLUP,TOLDWN,TOLCLS
42290 COMMON /BLK10/ ASHIFT,ASHFUM,ATSHF,BII,TOLUP,TOLDWN,TOLCLS
42300 COMMON /BLK11/ DIAG(4)
42310 COMMON /BLK12/ NTRY
42320 COMMON /BLK13/ DIF1,DIF2,DIF3,DIF4,TOLLOW,TOLHI,TOLRNG
42330 COMMON /BLPLOT/ KLI(29),$PLOTS,$MODAL
42340 COMMON /BLDATA/ TITLE,NC,IMODE,NDIMEN,IPRINT,LCHMAX,IC
42350 DIMENSION TITLE(18)
42360 **
42370 ** THE FOLLOWING BLOCK OF STATEMENTS SETS THE CONSTANTS FOR
42380 ** THE DOUBLE PRECISION PORTION OF THE ITERATION CALCULATIONS.
42390 **
42400 ONEDO = 1.00
42410 PTFIVE = 1.500
42420 SMALL = 1.00E-20
42430 TWOPI = 6.283185307179586400
42440 ZEROODC = 0.00
42450 **
42460 ** THE FOLLOWING BLOCK OF STATEMENTS SETS THE
42470 ** ITERATION AND CONVERGENCE PARAMETERS.
42480 **
42490 EPSSAIT = 1.0E-02
42500 EPSVIB = DBLE(EPS)
42510 IF(EPSVIB.EQ.ZEROODC) EPSSVEC = DBLE(EPS)
42520 IF($PLOTS.AND.(KMAX.GT.100)) KMAX=100
42530 KL = KMAX - 1
42540 KMAX1 = KMAX + 1
42550 KMAX2 = KMAX + 2
42560 IBEGIN = 1
42570 IGC = (IBEGIN * 4) - 3
42580 IEND = KMAX2
42590 IF(I8CFNL.LT.0) IEND = KMAX1
42600 ISTOP = IEND * 4
42610 ITR1 = ITRMAX
42620 IF(ITR2.EQ.0) ITR2 = ITR1 - 2
42630 NN2 = 2
42640 DIAG(4) = 0.0
42650 DO 1 I = 1,4
42660 1 WV(I,203) = DBLE(DIAG(I))
42670 **
42680 ** THE FOLLOWING BLOCK OF STATEMENTS SETS THE OPERATING PARAMETERS
42690 ** FOR THE FREQUENCY RANGE SEARCH MODE OF OPERATION.
42700 **
42710 TOLCLS = .4

```



```

C*****
IMPLICIT TWOPI, ZERO, PT FIVE, ONE, VREAL, VIMAG, EPSVIB, EPSVEC,
REAL*8
1 EPSAIT, WV, XV, YV, WT, SCALEW, SCALEX, SCALE3
1 COMMON/IBL7/ MNMAXO, MAXO(10), MAXSY(10), MODVIB(3,100), ITEM
1P(110)
COMMON/BL24/DG(4,4,4), RANGE(100,4), TOP, BOTTOM, DELSHF, TOLSHF, RZ(12)
COMMON/BL100/ TEEC, $DYNMC
COMMON/BL104/ WV(4,203), XV(4,203), YV(4,203), FILL(28), SHFTPT(3,100)
COMMON/BLK2/ IVIBES, IVB8
COMMON/BLK3/ TWCPPI, IBEGIN, IEND, ICC, ISTOP
COMMON/BLK4/ ZERO, PT FIVE, ONE, VREAL, VIMAG, AREAL
COMMON/BLK5/ $FLAG, $TAG, $DOVEC
COMMON/BLK6/ NJ, NK, I4, IRGCLO, NUMBER, ITWC
COMMON/BLK7/ SCALEX, SCALEW, SCALE3
COMMON/BLK8/ EPSVIB, EPSVEC, EPSAIT
COMMON/BLK9/ ITR1, ITR2
COMMON/BLK11/ DIAG(4)
COMMON/BLK12/ NTRY
COMMON/BLDATA/ TITLE, NC, IMODE, NDI, MEN, IPRINT, LCHMAX, IC
DIMENSION N.WT(812), Z(880), ITITLE(18)
EQUIVALENCE (WV(1,1), WT(1)), (WV(1,1), Z(1))
C*****
ITEST = 0
IF(IND.GE.7.AND.IND.LE.9) GO TO 22
IF(IND.EQ.17) GO TO 23
IF(IND.EQ.24)
GO TO 24
22 IF(VREAL.GT.ZERO) ITEST = 1 VREAL = -VREAL
IF(VREAL.LT.ZERO) VREAL = -VREAL
VREAL = DSORT(VREAL) / (DBLE(ITEED) * TWOPI)
GO TO 24
23 IF(VREAL.GT.ZERO) ITEST = 1
IF(VIMAG.GT.ZERO) ITEST = 2
IF(VIMAG.LT.ZERO) VREAL = -VREAL
IF(VIMAG.LT.ZERO) VIMAG = -VIMAG
VREAL = DSORT(VREAL) / (DBLE(ITEED) * TWOPI)
VIMAG = DSORT(VIMAG) / (DBLE(ITEED) * TWOPI)
C*****
24 GO TO (1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21), IND
C*****
C SLOT 12 IS AVAILABLE FOR FUTURE USE.
C*****
1 WRITE(6,201) MODVIB(2,IVB)
WRITE(6,202) SHFTPT(1,IVB), SHFTPT(2,IVB), BCTTCM, TOP
WRITE(6,203) DIAG
IF($DOVEC) WRITE(6,207) EPSVEC
IF(.NOT. $DOVEC) WRITE(6,208)
RETURN
C*****

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201 FORMAT('1',42X,'THIS IS A FREQUENCY RANGE SEARCH FOR HARMONIC',I3)
202 FORMAT('0',24X,'BOTTOM OF RANGE IS',E12.4,' HZ',I2X,'TOP OF RANGE
3 IS',E12.4,' HZ',/35X,'BOTTOM =',E12.4,' HZ',I2X,'TOP =',E12.4)
203 FORMAT('0',41X,'DIAGONAL OF MASS MATRIX IS (',4F3.0,' )')
207 FORMAT('0',42X,'THE CONVERGENCE TEST ON THE VECTOR WILL BE PERFORM
1ED',/50X,'CONVERGENCE CRITERION IS',E10.2)
208 FORMAT('0',38X,'THE CONVERGENCE TEST ON THE VECTOR WILL NOT BE PER
2FORMED')
2 WRITE(6,204) ITRI
2 RETURN 1
204 FORMAT('0',44X,'CHECK PERMISSIBLE NUMBER OF ITERATIONS (',I2,'')
3 WRITE(6,205) EPSVIB
205 RETURN 1
205 FORMAT('0',51X,'EPS IS VERY SMALL (',E9.2,'')
4 WRITE(6,206)
205 RETURN 1
206 FORMAT('0',55X,'CHECK RANGE END POINTS')
5 WRITE(6,219) MODVIB(2,IVB)
6 WRITE(6,203) DIAG
WRITE(6,203) DIAG
IF($DOVEC) WRITE(6,207) EPSVEC
IF(.NOT.$DOVEC) WRITE(6,208)
206 RETURN 1
219 FORMAT('1',41X,'THE LOWEST FREQUENCY IN HARMONIC',I4,' IS DETERMIN
6ED')
6 WRITE(6,220) MODVIB(1,IVB),MODVIB(2,IVB)
7 WRITE(6,203) DIAG
IF($DOVEC) WRITE(6,207) EPSVEC
IF(.NOT.$DOVEC) WRITE(6,208)
206 RETURN 1
220 FORMAT('1',41X,I2,' SHIFT POINT(S) FOR HARMONIC',I3,' IS(ARE) PROV
7ICED')
7 WRITE(6,209) NK
WRITE(6,210) VREAL
IF(ITEREST.EQ.1) WRITE(6,221)
WRITE(6,224) SCALEW,SCALEX,SCALE3
NJ = 0
209 RETURN 1
209 FORMAT('0',36X,'NO CONVERGENCE TO A REAL EIGENVALUE AFTER ',I5,' I
1TERATIONS')
210 FORMAT('0',38X,'RAYLEIGH QUOTIENT FREQUENCY =',E23.14,' HZ')
221 FORMAT('0',38X,'THE FREQUENCY IS IMAGINARY.')
224 FORMAT('0',34X,'THE LAST NEXT TO NEXT TO LAST EIG
5ENVALUES ARE',/35X,3E21.12)
8 WRITE(6,209) NK
WRITE(6,210) VREAL
IF(ITEREST.EQ.1) WRITE(6,221)
WRITE(6,224) SCALEW,SCALEX,SCALE3
209 RETURN 1

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43990
44000
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44020
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44080
44090
44100
44110


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9  WRITE(6,211) NK
   WRITE(6,210) VREAL
   IF (ITEST .EQ. 1) WRITE(6,221)
   DO 91 I = 1GO, ISTOP
     Z(I) = SNGL(WT(I))
     CALL OUTP(IMODE)
     RETURN 1
211  FORMAT('0',47X,'CONVERGED SOLUTION. ITERATIONS =',I6)
10  WRITE(6,301) BOTTOM
   RETURN 1
301  FORMAT('0',50X,'THE RANGE SIZE HAS BEEN REDUCED.'/51X,'BOTTOM OF R
11  RANGE IS NOW',E14.6)
   WRITE(6,302)
   RETURN 1
302  FORMAT('0',55X,'RANGE HAS BEEN COVERED')
12  WRITE(6,303) NTRY
   RETURN 1
303  FORMAT('0',38X,'UNABLE TO DETERMINE A MINIMUM FREQUENCY AFTER ',I
13  '3', 'TRIES.')
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```

13  CONTINUE
   RETURN 1
14  WRITE(6,305) NTRY
   RETURN 1
305  FORMAT('0',38X,'UNABLE TO DETERMINE A MAXIMUM FREQUENCY AFTER ',I
13  '3', 'TRIES.')
```

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15  WRITE(6,304) TOP
   RETURN 1
304  FORMAT('0',50X,'THE RANGE SIZE HAS BEEN REDUCED.'/51X,'TOP OF RANG
2E IS NOW',E14.6)
16  WRITE(6,212) NK,VREAL,VIMAG
   WRITE(6,225) SCALEW,SCALEX,SCALE3
   NJ = 0
   RETURN 1
212  FORMAT('0',47X,'NO CONVERGENCE AFTER',I6,' ITERATIONS.'/42X,'EIGEN
5  VALUES(S) ARE',2E15.6)
225  FORMAT('0',29X,'THE LAST, NEXT TO LAST AND NEXT TO NEXT TO LAST VE
4  CTOR ELEMENT MAXIMUMS ARE',/35X,3D21.12)
17  WRITE(6,213)
   WRITE(6,214) NK,VREAL,VIMAG
   IF (ITEST .EQ. 1) WRITE(6,222)
   IF (ITEST .EQ. 2) WRITE(6,223)
   RETURN 1
213  FORMAT('0',45X,'CONVERGED SOLUTION - TWO REAL EIGENVALUES',/21X,'AN
1  INCREASE IN THE CONVERGENCE CRITERIA(EPS) AND/OR AN INCREASE IN T
2  HE PERMISSIBLE NUMBER OF',/16X,'ITERATIONS(ITRMAX) IS RECOMMENDED A
3  S A POSSIBLE SOLUTION TO THE PROBLEM OF A POORLY CONDITIONED MATRI
4  X,')
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214  FORMAT('0',29X,'ITERATIONS ARE',I6,10X,'FREQUENCIES, IN HZ, ARE',2
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44480
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44590


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8E16.6)
222 FORMAT('0',63X,'THE FIRST FREQUENCY IS IMAGINARY.')
```

223 FORMAT('0',63X,'BOTH FREQUENCIES ARE IMAGINARY.')

18 WRITE(6,215) NK,VREAL,VIMAG

RETURN 1

215 FORMAT('0',46X,'CONVERGED SOLUTION - COMPLEX EIGENVALUE',/34X,'ITER

1ATIONS ARE',16,10X,'EIGENVALUE IS',4X,2E15.6)

19 WRITE(6,216) NUMBER

RETURN 1

216 FORMAT('0',51X,15,' FREQUENCIES HAVE BEEN FOUND')

20 WRITE(6,217) BOTTOM,RANGE(1,1),RANGE(1,2)

RETURN 1

217 FORMAT('0',47X,'BOTTOM =',E12.4/48X,'LOWEST EIGENVALUE (RANGE(1,1)

2) =',E14.6/48X,'RANGE(1,2) =',E12.4)

21 WRITE(6,218) TOP,RANGE(1,4),RANGE(1,3)

RETURN 1

218 FORMAT('0',47X,'TOP =',E12.4/48X,'HIGHEST EIGENVALUE (RANGE(1,4))

3 =',E14.6/48X,'RANGE(1,3) =',E12.4)

END

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44600
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44670
44680
44690
44700
44710
44720
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44750
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44770

```

SUBROUTINE START(K)
C *****
C SUBROUTINE START INITIALIZES THE EIGENVALUES AND EIGENVECTORS
C PRIOR TO THE START OF EACH ITERATION.
C *****
REAL*8 TWOPI,ZERODD,PTFIVE,ONEDO,SMALL,VREAL,VIMAG,SCALEW,SCALEX,SCALEY,
1SCALEZ,WV,WT,XV,XT,YV,YT,TEMP
COMMON/BLK104/ WV(4,203),XV(4,203),FILL(28),SHFTPT(3,100)
COMMON/BLK3/ TWOPI,18FIVE,IEND,IGD,ISTOP
COMMON/BLK4/ ZERODD,PTFIVE,ONEDO,SMALL,VREAL,VIMAG,AREAL
COMMON/BLK6/NJ,NK,I4,IRGOLD,NUMBER,ITWO
COMMON/BLK7/ SCALEX,SCALEY,SCALEZ
DIMENSION WT(812),XT(812),YT(812)
EQUIVALENCE (WV(1,1),WT(1)),(XV(1,1),XT(1)),(YV(1,1),YT(1))
C *****
NJ = 0
NK = 0
ITWO = 0
SCALEW = 1
SCALEX = 1
SCALEY = 1
SCALEZ = 1
VIMAG = 1
GO TO (1,3,3),K
1 DO 2 I = 1,IGD,I STOP
2 WT(I) = 1
3 TEMP = 1

```

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44800
44810
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45010
45020
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45040

45050
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45090
45100
45110
45120
45130
45140

```

4 I = IGC,ISTCP
TEMP = DMAX1(DABS(YT(I)),TEMP)
IF(TEMP .LT. (1.C-40)) GO TO 1
TEMP = ONECC / TEMP
DC 5 I = IGC,ISTCP
WT(I) = YT(I) * TEMP
DC 7 I = IGC,ISTCP
XT(I) = CNECC
RETURN
END

```

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45490
45500

```

SUBROUTINE MATINV(A,N,B,M,DETERM,IPIVOT,INDEX,NMAX,ISCALE)
C-----
C THIS SUBROUTINE SOLVES THE MATRIX EQUATION AX=B, WHERE A IS
C A SQUARE COEFFICIENT MATRIX AND B IS A MATRIX OF CONSTANT VEC-
C TORS.
C A(INVERSE) IS ALSO OBTAINED AND THE DETERMINANT OF A IS AVAIL-
C ABLE.
C THE FOLLOWING MUST BE DIMENSIONED IN THE CALLING PROGRAM:
C IPIVOT(N MAX), INDEX(N MAX,2), A(N MAX,N MAX), B(N MAX,N MAX)
C WHERE:
C A = NAME OF 2-DIMENSIONAL ARRAY TO BE INVERTED
C N = ORDER OF A (N<=NMAX)
C B = NAME OF 2-DIMENSIONAL ARRAY TO BE MULTIPLIED
C BY A(INVERSE)
C M = NUMBER OF COLUMN VECTORS IN B
C NOTE: M = 0 SIGNALS INVERSION ONLY)
C IPIVOT = TEMPORARY STORAGE BLOCK
C INDEX = TEMPORARY STORAGE BLOCK
C NMAX = MAXIMUM ORDER OF A (AS DIMENSIONED IN THE
C CALLING PROGRAM)
C DETERM = VALUE OF DETERMINANT AS GIVEN BELOW
C ISCALE = USED IN FORMULA BELOW
C DETERMINANT(A) = (10**18) * ISCALE*(DETERM)
C
C A(INVERSE) IS STORED IN A
C A(INVERSE) IS STORED IN B
C
C DIMENSION IPIVOT(N), A(NMAX,N), B(NMAX,M), INDEX(NMAX,2)
C EQUIVALENCE (IROW,JROW), (ICOL,JCOL), (AMAX,I,SWAP)
C-----
C INITIALIZATION
C
5 ISCALE=0
6 RI=10.0**18
7 R2=1.0/R1

```



```

10 CTERM=1.0
15 DO 20 J=1,N
20 IPIVOT(J)=0
30 DO 550 I=1,N
    SEARCH FOR PIVOT ELEMENT
40 AMAX=0.0
45 DO 105 J=1,N
50 IF (IPIVOT(J)-1) 60, 105, 60
60 DO 100 K=1,N
70 IF (IPIVOT(K)-1) 80, 100, 740
80 IF (ABS(AMAX)-ABS(A(J,K)))85, 100, 100
85 IROW=J
90 ICOLUM=K
95 AMAX=A(J,K)
100 CONTINUE
110 IPIVOT(ICOLUM)=IPIVOT(ICOLUM)+1
    INTERCHANGE ROWS TO PUT PIVOT ELEMENT ON DIAGONAL
130 IF (IROW-ICOLUM) 140, 260, 140
140 DETERM=-CTERM
150 DO 200 L=1,N
160 SWAP=A(IROW,L)
170 A(IROW,L)=A(ICOLUM,L)
200 A(ICOLUM,L)=SWAP
205 IF (M) 260, 260, 210
210 DO 250 L=1,M
220 SWAP=B(IROW,L)
230 B(IROW,L)=B(ICOLUM,L)
250 B(ICOLUM,L)=SWAP
260 INDEX(I,1)=IROW
270 INDEX(I,2)=ICOLUM
310 PIVOT=A(ICOLUM,ICOLUM)
    SCALE THE DETERMINANT
1000 PIVOTI=PIVOT
1005 IF (ABS(DETERM)-R1) 1030, 1010, 1010
1010 DETERM=DETERM/R1
    ISCALE=ISCALE+1
1020 IF (ABS(DETERM)-R1) 1060, 1020, 1020
    DETERM=DETERM/R1
    ISCALE=ISCALE+1
    GO TO 1060
1030 IF (ABS(DETERM)-P2) 1040, 1040, 1060

```



```

1040 DETERM=DETERM*R1
1050 ISCALE=ISCALE-1
1060 IF(ABS(DETERM)-R2)1050,1060
1070 DETERM=DETERM*R1
1080 ISCALE=ISCALE-1
1090 IF(ABS(PIVOTI)-R1)1050,1070,1070
1100 PIVCTI=PIVCTI/R1
1110 ISCALE=ISCALE+1
1120 IF(ABS(PIVOTI)-R1)1050,1080
1130 PIVCTI=PIVCTI/R1
1140 ISCALE=ISCALE+1
1150 GO TO 320
1160 IF(ABS(PIVOTI)-R2)2000,2000,320
1170 PIVCTI=PIVCTI*R1
1180 ISCALE=ISCALE-1
1190 IF(ABS(PIVOTI)-R2)2010,2010,320
1200 PIVOTI=PIVOTI*R1
1210 ISCALE=ISCALE-1
1220 DETERM=DETERM*PIVOTI
1230
1240 DIVIDE PIVOT ROW BY PIVOT ELEMENT
1250
1260 A(ICOLU,ICOLU)=1.0
1270 DO 350 L=1,N
1280 A(ICOLU,L)=A(ICOLU,L)/PIVOT
1290 IF(N) 380, 380, 360
1300 DO 370 L=1,M
1310 B(ICOLU,L)=B(ICOLU,L)/PIVOT
1320
1330 REDUCE NON-PIVOT ROWS
1340
1350 DO 550 L1=1,N
1360 IF(L1-ICOLU) 400, 550, 400
1370 T=A(L1,ICOLU)
1380 A(L1,ICOLU)=0.0
1390 DO 450 L=1,N
1400 A(L1,L)=A(L1,L)-A(ICOLU,L)*T
1410 IF(M) 550, 550, 460
1420 DO 500 L=1,N
1430 B(L1,L)=B(L1,L)-B(ICOLU,L)*T
1440 CONTINUE
1450
1460 INTERCHANGE COLUMNS
1470
1480 DO 710 I=1,N
1490 L=N+1-I
1500 IF (INDEX(L,1)-INDEX(L-2)) 620, 710, 630
1510 JROW=INDEX(L,1)

```



```

640 JCOLUM=INDEX(L,2)
650 DO 705 K=1,N
660 SWAP=A(K,JROW)
670 A(K,JROW)=A(K,JCOLUM)
700 A(K,JCOLUM)=SWAP
705 CONTINUE
710 CONTINUE
740 RETURN
750 END

```

SUBROUTINE FLYNIV

WR	RR	IT	EE
(6.1)	(6.1)	(6.1)	(6.1)
WR	RR	IT	EE
(6.2)	(6.2)	(6.2)	(6.2)
WR	RR	IT	EE
(6.3)	(6.3)	(6.3)	(6.3)
WR	RR	IT	EE
(6.4)	(6.4)	(6.4)	(6.4)
WR	RR	IT	EE
(6.5)	(6.5)	(6.5)	(6.5)
WR	RR	IT	EE
(6.6)	(6.6)	(6.6)	(6.6)
WR	RR	IT	EE
(6.7)	(6.7)	(6.7)	(6.7)
WR	RR	IT	EE
(6.8)	(6.8)	(6.8)	(6.8)
WR	RR	IT	EE
(6.9)	(6.9)	(6.9)	(6.9)
WR	RR	IT	EE
(6.10)	(6.10)	(6.10)	(6.10)
WR	RR	IT	EE
(6.11)	(6.11)	(6.11)	(6.11)
WR	RR	IT	EE
(6.12)	(6.12)	(6.12)	(6.12)
WR	RR	IT	EE
(6.13)	(6.13)	(6.13)	(6.13)
WR	RR	IT	EE
(6.14)	(6.14)	(6.14)	(6.14)
WR	RR	IT	EE
(6.15)	(6.15)	(6.15)	(6.15)
WR	RR	IT	EE
(6.16)	(6.16)	(6.16)	(6.16)
WR	RR	IT	EE
(6.17)	(6.17)	(6.17)	(6.17)
WR	RR	IT	EE
(6.18)	(6.18)	(6.18)	(6.18)
WR	RR	IT	EE
(6.19)	(6.19)	(6.19)	(6.19)
WR	RR	IT	EE
(6.20)	(6.20)	(6.20)	(6.20)
WR	RR	IT	EE
(6.21)	(6.21)	(6.21)	(6.21)
WR	RR	IT	EE
(6.22)	(6.22)	(6.22)	(6.22)
WR	RR	IT	EE
(6.23)	(6.23)	(6.23)	(6.23)
WR	RR	IT	EE
(6.24)	(6.24)	(6.24)	(6.24)
WR	RR	IT	EE
(6.25)	(6.25)	(6.25)	(6.25)
WR	RR	IT	EE
(6.26)	(6.26)	(6.26)	(6.26)
WR	RR	IT	EE
(6.27)	(6.27)	(6.27)	(6.27)
WR	RR	IT	EE
(6.28)	(6.28)	(6.28)	(6.28)
WR	RR	IT	EE
(6.29)	(6.29)	(6.29)	(6.29)
WR	RR	IT	EE
(6.30)	(6.30)	(6.30)	(6.30)
WR	RR	IT	EE
(6.31)	(6.31)	(6.31)	(6.31)
WR	RR	IT	EE
(6.32)	(6.32)	(6.32)	(6.32)
WR	RR	IT	EE
(6.33)	(6.33)	(6.33)	(6.33)
WR	RR	IT	EE
(6.34)	(6.34)	(6.34)	(6.34)

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13. ABSTRACT

A digital computer program known as SATANS-III is developed as a modification to the program SATANS-I, incorporating the capability to perform free vibration analyses for the natural frequencies and modes of thin, elastic shells of revolution. The geometric and material properties of the shell may vary along the meridian. SATANS-III retains the SATANS-I capability of performing geometrically nonlinear static and dynamic analyses of arbitrarily loaded shells. The free vibration analysis employs the inverse iteration method with spectral shifts, including the capability to search a specific range of frequencies. Several example problems are solved to illustrate the program's validity and accuracy. A user's manual for SATANS-III is presented. In addition, the problem of handling a large, strongly banded, unsymmetric and occasionally singular stiffness matrix in conjunction with a singular mass matrix is treated. A discussion of several solution procedures with respect to this problem is given.

14. KEY WORDS	LINK A		LINK B		LINK C	
	ROLE	WT	ROLE	WT	ROLE	WT
SHELLS						
SHELLS OF REVOLUTION						
FREQUENCIES						
NATURAL FREQUENCIES						
NATURAL FREQUENCIES OF SHELLS						
VIBRATION						
FREE VIBRATION						
FREE VIBRATION OF SHELLS						
MODES						
MODES OF VIBRATION						
NATURAL MODES OF VIBRATION						
NATURAL MODES OF VIBRATION OF SHELLS						
STRUCTURAL VIBRATIONS						
FREE VIBRATIONS OF STRUCTURES						
EIGENVALUES						
REAL EIGENVALUES						
UNSYMMETRIC MATRICES						
EIGENVALUES OF UNSYMMETRIC MATRICES						
BUCKLING OF SHELLS						
STRUCTURAL ANALYSIS						
SATANS						
SATANS-III						

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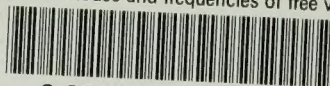
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